MSP430® Peripheral Driver Library for F5xx and F6xx Devices

USER'S GUIDE

Copyright © 2013 Texas Instruments Incorporated.

Copyright

Copyright © 2013 Texas Instruments Incorporated. All rights reserved. MSP430 and 430ware are registered trademarks of Texas Instruments. Other names and brands may be claimed as the property of others.

Please be aware that an important notice concerning availability, standard warranty, and use in critical applications of Texas Instruments semiconductor products and disclaimers thereto appears at the end of this document.

Texas Instruments
Post Office Box 655303
Dallas, TX 75265
http://www.ti.com/msp430

Revision Information

This is version 1.40.01.00 of this document, last updated on 2013-05-20$_0$9 : 07 : 07$_$0500.

Table of Contents

Copyright . . . 2
Revision Information . . . 2
1 Introduction . . . 5
2 Navigating to driverlib through CCS Resource Explorer . . . 7
3 How to create a new user project that uses Driverlib . . . 17
4 How to include driverlib into your existing project . . . 19
5 10-Bit Analog-to-Digital Converter (ADC10_A) . . . 23
5.1 Introduction . . . 23
5.2 API Functions . . . 23
5.3 Programming Example . . . 24
6 12-Bit Analog-to-Digital Converter (ADC12) . . . 25
6.1 Introduction . . . 25
6.2 API Functions . . . 25
6.3 Programming Example . . . 26
7 Advanced Encryption Standard (AES) . . . 29
7.1 Introduction . . . 29
7.2 API Functions . . . 29
7.3 Programming Example . . . 30
8 Battery Backup System . . . 31
8.1 Introduction . . . 31
8.2 API Functions . . . 31
8.3 Programming Example . . . 31
9 Comparator (COMP_B) . . . 33
9.1 Introduction . . . 33
9.2 API Functions . . . 33
9.3 Programming Example . . . 34
10 Cyclical Redundancy Check (CRC) . . . 35
10.1 Introduction . . . 35
10.2 API Functions . . . 35
10.3 Programming Example . . . 35
11 12-bit Digital-to-Analog Converter (DAC12_A) . . . 37
11.1 Introduction . . . 37
11.2 API Functions . . . 37
11.3 Programming Example . . . 38
12 Direct Memory Access (DMA) . . . 39
12.1 Introduction . . . 39
12.2 API Functions . . . 39
12.3 Programming Example . . . 40
13 EUSCI Universal Asynchronous Receiver/Transmitter (EUSCI_A_UART) . . . 41
13.1 Introduction . . . 41
13.2 API Functions . . . 41
13.3 Programming Example . . . 42
14 EUSCI Synchronous Peripheral Interface (EUSCI_A_SPI) . . . 43
14.1 Introduction . . . 43
14.2 Functions . . . 43
14.3 Programming Example . . . 44
15 EUSCI Synchronous Peripheral Interface (EUSCI_B_SPI) . . . 45
15.1 Introduction . . . 45
15.2 Functions . . . 45
15.3 Programming Example . . . 46
16 EUSCI Inter-Integrated Circuit (EUSCI_B_I2C) . . . 47
16.1 Introduction . . . 47
16.2 API Functions . . . 49
16.3 Programming Example . . . 50
17 Flash Memory Controller . . . 51
17.1 Introduction . . . 51
17.2 API Functions . . . 51
17.3 Programming Example . . . 52
18 GPIO . . . 53
18.1 Introduction . . . 53

18.2 API Functions . . . 54
18.3 Programming Example . . . 54
19 LDO-PWR . . . 57
19.1 Introduction . . . 57
19.2 API Functions . . . 57
19.3 Programming Example . . . 58
20 32-Bit Hardware Multiplier (MPY32) . . . 61
20.1 Introduction . . . 61
20.2 API Functions . . . 61
20.3 Programming Example . . . 62
21 Port Mapping Controller . . . 63
21.1 Introduction . . . 63
21.2 API Functions . . . 63
21.3 Programming Example . . . 63
22 Power Management Module (PMM) . . . 65
22.1 Introduction . . . 65
22.2 API Functions . . . 66
22.3 Programming Example . . . 68
23 RAM Controller . . . 69
23.1 Introduction . . . 69
23.2 API Functions . . . 69
23.3 Programming Example . . . 69
24 Internal Reference (REF) . . . 71
24.1 Introduction . . . 71
24.2 API Functions . . . 71
24.3 Programming Example . . . 72
25 Real-Time Clock (RTC) . . . 75
25.1 Introduction . . . 75
25.2 API Functions . . . 75
25.3 Programming Example . . . 76
26 Real-Time Clock (RTC) . . . 77
26.1 Introduction . . . 77
26.2 API Functions . . . 77
26.3 Programming Example . . . 78
27 Real-Time Clock (RTC_C) . . . 79
27.1 Introduction . . . 79
27.2 API Functions . . . 79
27.3 Programming Example . . . 80
28 24-Bit Sigma Delta Converter (SD24_B) . . . 81
28.1 Introduction . . . 81
28.2 API Functions . . . 81
28.3 Programming Example . . . 82
29 SFR Module . . . 83
29.1 Introduction . . . 83
29.2 API Functions . . . 83
29.3 Programming Example . . . 83
30 SYS Module . . . 85
30.1 Introduction . . . 85
30.2 API Functions . . . 85
30.3 Programming Example . . . 86
31 TEC . . . 87
31.1 Introduction . . . 87
31.2 API Functions . . . 87
31.3 Programming Example . . . 88
32 TIMER_A . . . 89
32.1 Introduction . . . 89
32.2 API Functions . . . 90
32.3 Programming Example . . . 90
33 TIMER_B . . . 93
33.1 Introduction . . . 93
33.2 API Functions . . . 94
33.3 Programming Example . . . 95
34 TIMER_D . . . 97

34.1 Introduction . . . 97
34.2 API Functions . . . 98
34.3 Programming Example . . . 100
35 Tag Length Value . . . 101
35.1 Introduction . . . 101
35.2 API Functions . . . 101
35.3 Programming Example . . . 101
36 Unified Clock System (UCS) . . . 103
36.1 Introduction . . . 103
36.2 API Functions . . . 104
36.3 Programming Example . . . 105
37 USCI Universal Asynchronous Receiver/Transmitter (USCI_A_UART) . . . 107
37.1 Introduction . . . 107
37.2 API Functions . . . 107
37.3 Programming Example . . . 108
38 USCI Synchronous Peripheral Interface (USCI_A_SPI) . . . 111
38.1 Introduction . . . 111
38.2 API Functions . . . 111
38.3 Programming Example . . . 112
39 USCI Synchronous Peripheral Interface (USCI_B_SPI) . . . 115
39.1 Introduction . . . 115
39.2 API Functions . . . 115
39.3 Programming Example . . . 116
40 USCI Inter-Integrated Circuit (USCI_B_I2C) . . . 119
40.1 Introduction . . . 119
40.2 API Functions . . . 121
40.3 Programming Example . . . 122
41 WatchDog Timer (WDT_A) . . . 123
41.1 Introduction . . . 123
41.2 API Functions . . . 123
41.3 Programming Example . . . 123
IMPORTANT NOTICE . . . 126

1 Introduction

The Texas Instruments® MSP430® Peripheral Driver Library is a set of drivers for accessing the peripherals found on the MSP430 5xx/6xx family of microcontrollers. While they are not drivers in the pure operating system sense (that is, they do not have a common interface and do not connect into a global device driver infrastructure), they do provide a mechanism that makes it easy to use the device's peripherals.

The capabilities and organization of the drivers are governed by the following design goals:

- They are written entirely in C except where absolutely not possible.
- They demonstrate how to use the peripheral in its common mode of operation.
- They are easy to understand.
- They are reasonably efficient in terms of memory and processor usage.
- They are as self-contained as possible.
- Where possible, computations that can be performed at compile time are done there instead of at run time.
- They can be built with more than one tool chain.

Some consequences of these design goals are:

- The drivers are not necessarily as efficient as they could be (from a code size and/or execution speed point of view). While the most efficient piece of code for operating a peripheral would be written in assembly and custom tailored to the specific requirements of the application, further size optimizations of the drivers would make them more difficult to understand.
- The drivers do not support the full capabilities of the hardware. Some of the peripherals provide complex capabilities which cannot be utilized by the drivers in this library, though the existing code can be used as a reference upon which to add support for the additional capabilities.
- The APIs have a means of removing all error checking code. Because the error checking is usually only useful during initial program development, it can be removed to improve code size and speed.

For many applications, the drivers can be used as is. But in some cases, the drivers will have to be enhanced or rewritten in order to meet the functionality, memory, or processing requirements of the application. If so, the existing driver can be used as a reference on how to operate the peripheral.

Each MSP430ware driverlib API takes in the base address of the corresponding peripheral as the first parameter. This base address is obtained from the msp430 device specific header files (or from the device datasheet). The example code for the various peripherals show how base address is used. When using CCS, the eclipse shortcut "Ctrl + Space" helps. Type __MSP430 and "Ctrl + Space", and the list of base addresses from the included device specific header files is listed.

The following tool chains are supported:

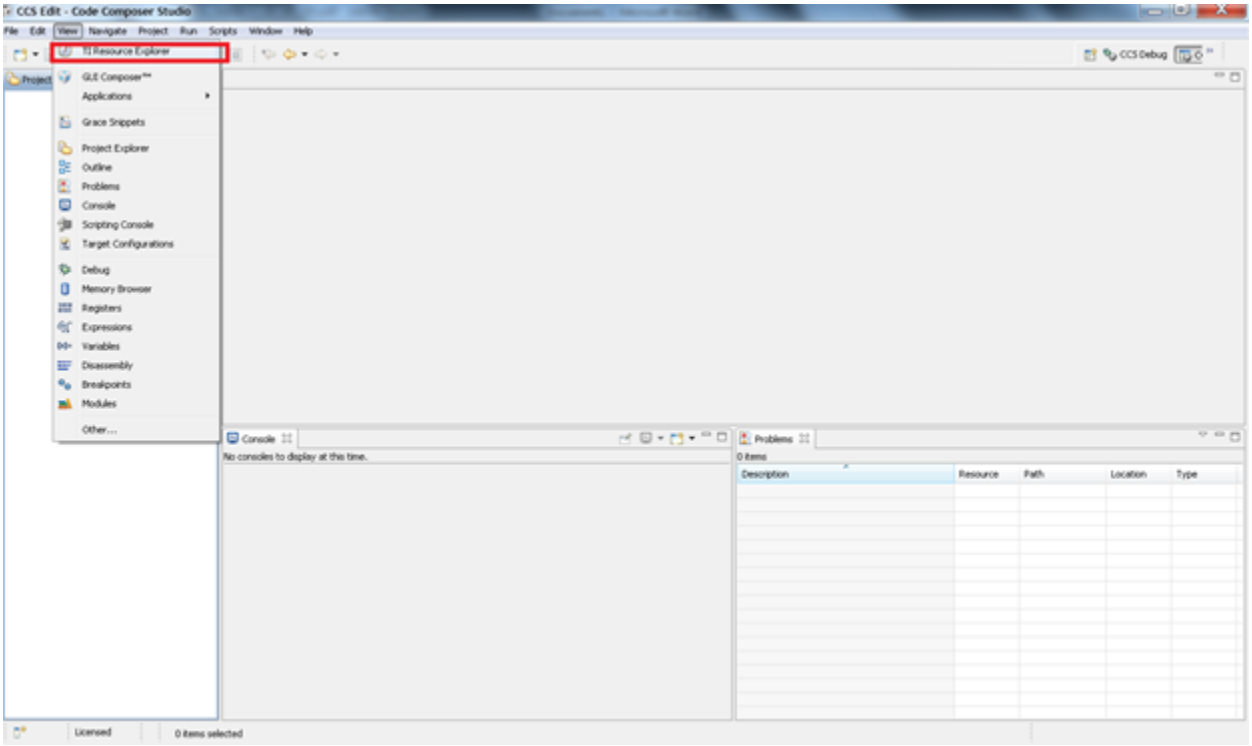
- IAR Embedded Workbench®
- Texas Instruments Code Composer Studio™

Using assert statements to debug

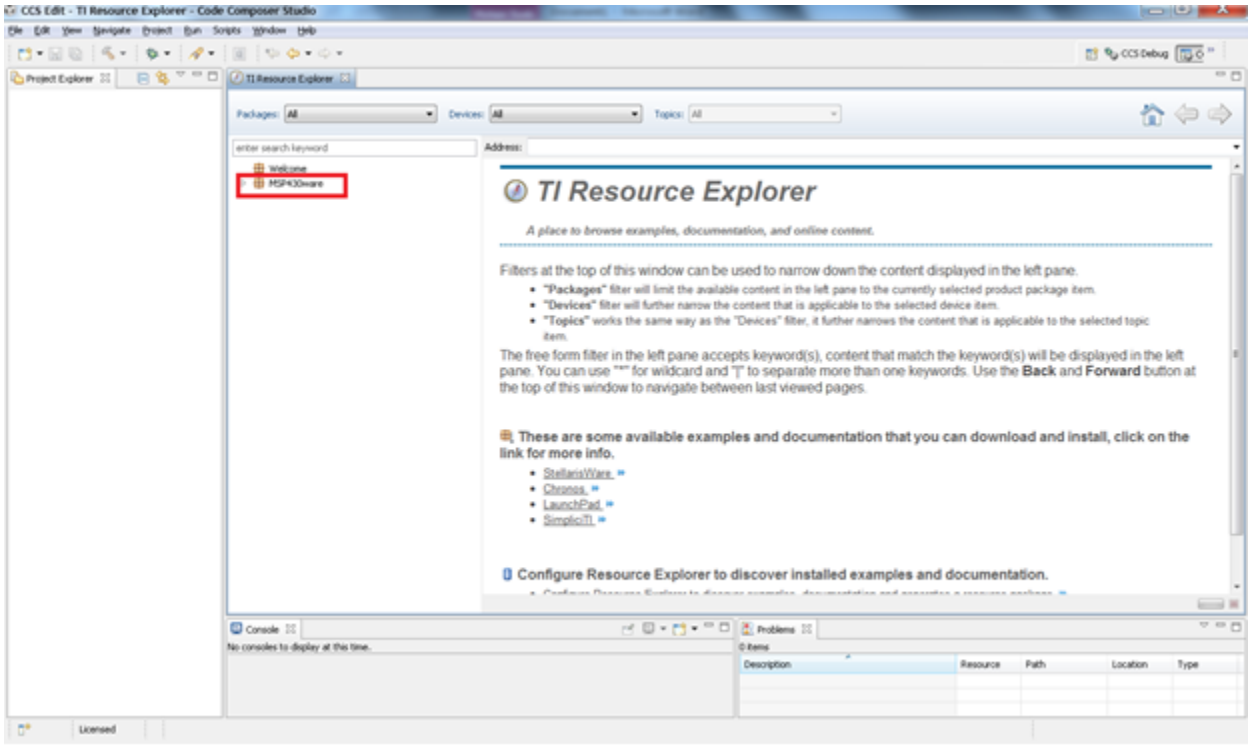
Assert statements are disabled by default. To enable the assert statement edit the hw_regaccess.h file in the inc folder. Comment out the statement define NDEBUG -> //define NDEBUG Asserts in CCS work only if the project is optimized for size.

2 Navigating to driverlib through CCS Resource Explorer

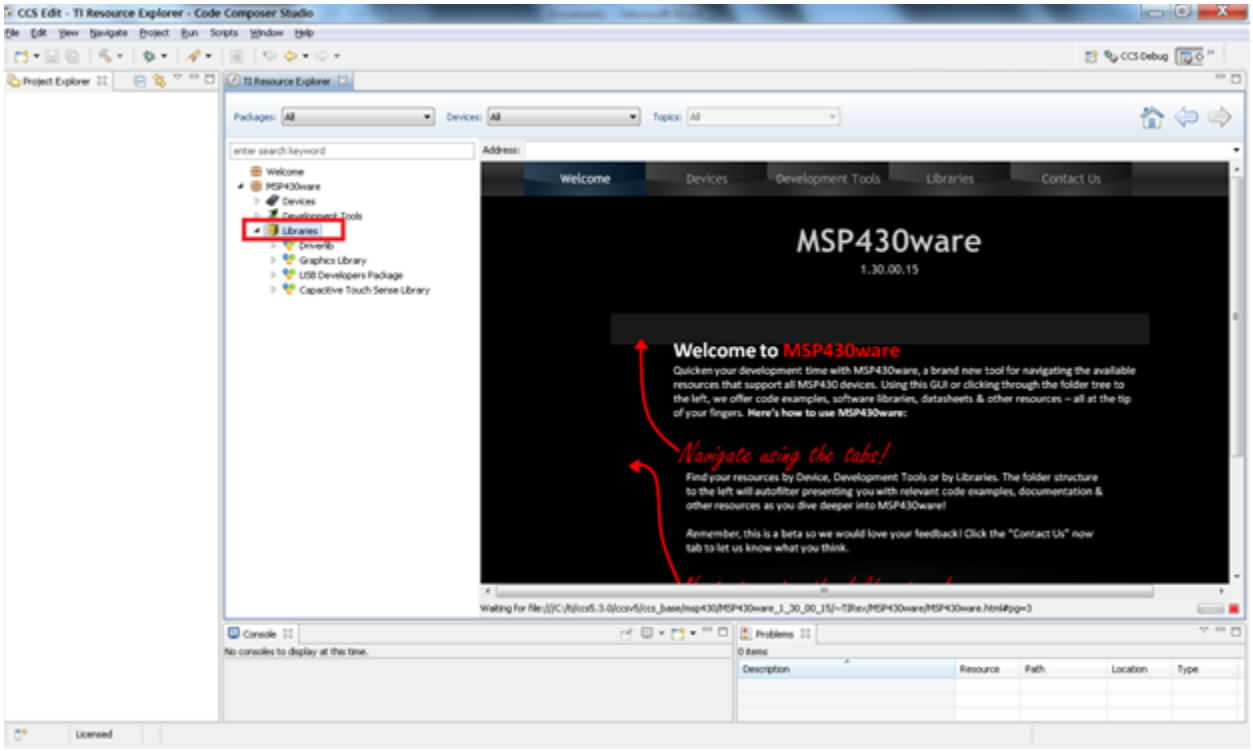
In CCS, click View->TI Resource Explorer

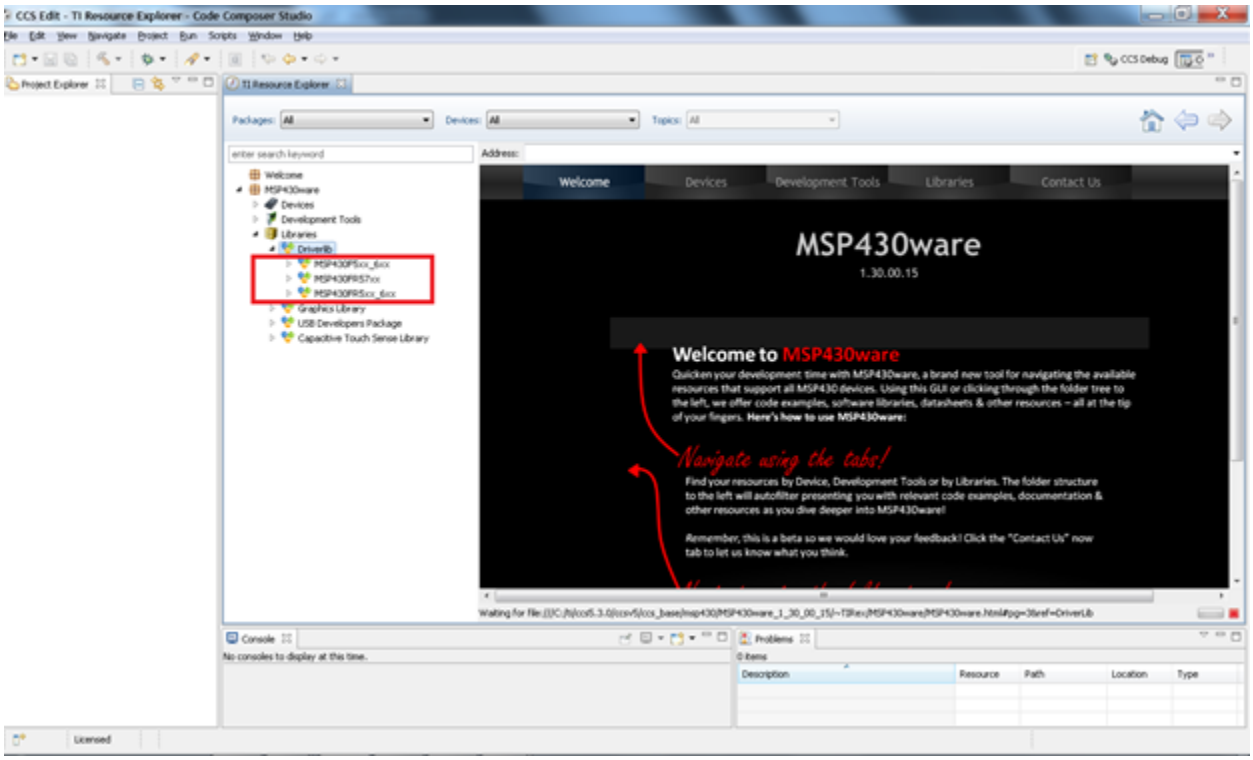


In Resource Explorer View, click on MSP430ware

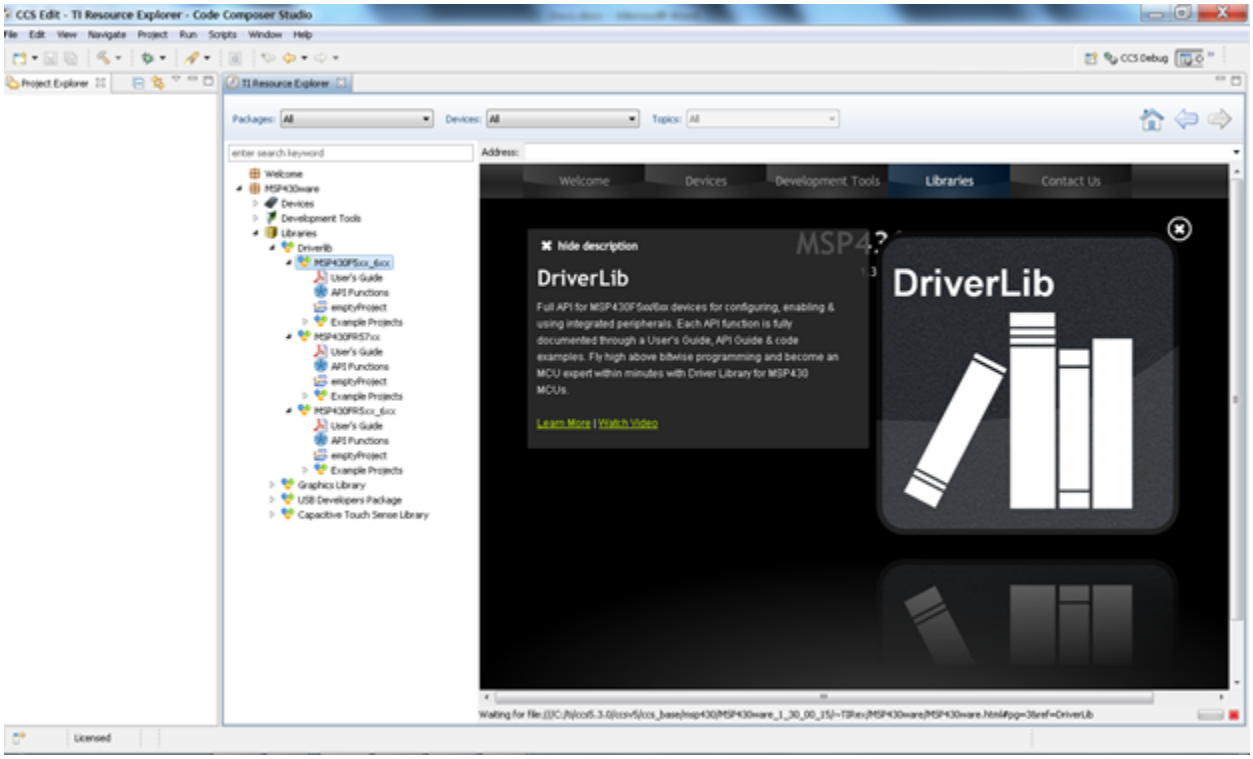

CCS Edit - TI Resource Explorer - Code Composer Studio
TI Resource Explorer
A place to browse examples, documentation, and online content.
Filters at the top of this window can be used to narrow down the content displayed in the left pane.
"Packages" filter will limit the available content in the left pane to the currently selected product package item.
"Devices" filter will further narrow the content that is applicable to the selected device item.
"Topics" works the same way as the "Devices" filter, it further narrows the content that is applicable to the selected topic item.
The free form filter in the left pane accepts keyword(s), content that match the keyword(s) will be displayed in the left pane. You can use "*" for wildcard and "|" to separate more than one keywords. Use the Back and Forward button at the top of this window to navigate between last viewed pages.
These are some available examples and documentation that you can download and install, click on the link for more info.
StellarisWare
Chronos
LaunchPad
SimpliciTI
Configure Resource Explorer to discover installed examples and documentation.

Clicking MSP430ware takes you to the introductory page. The version of the latest MSP430ware installed is available in this page. In this screenshot the version is 1.30.00.15 The various software, collateral, code examples, datasheets and user guides can be navigated by clicking the different topics under MSP430ware. To proceed to driverlib, click on Libraries->Driverlib as shown in the next two screenshots.

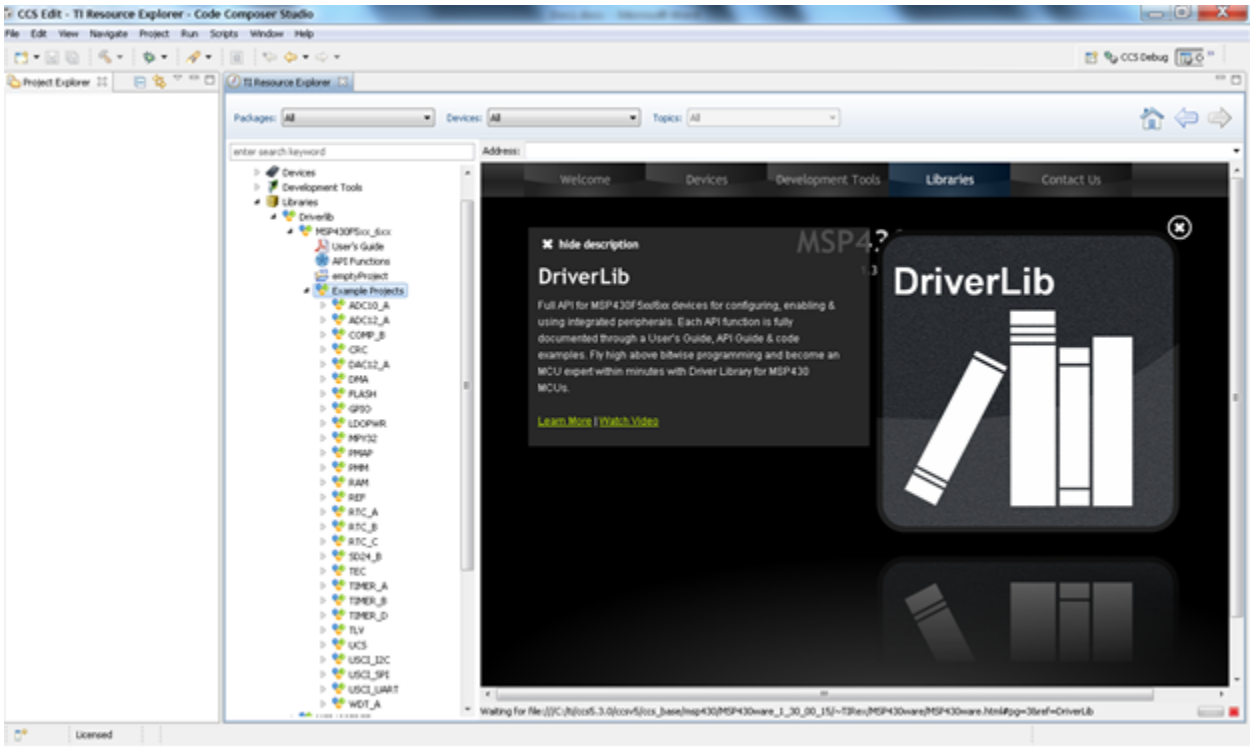




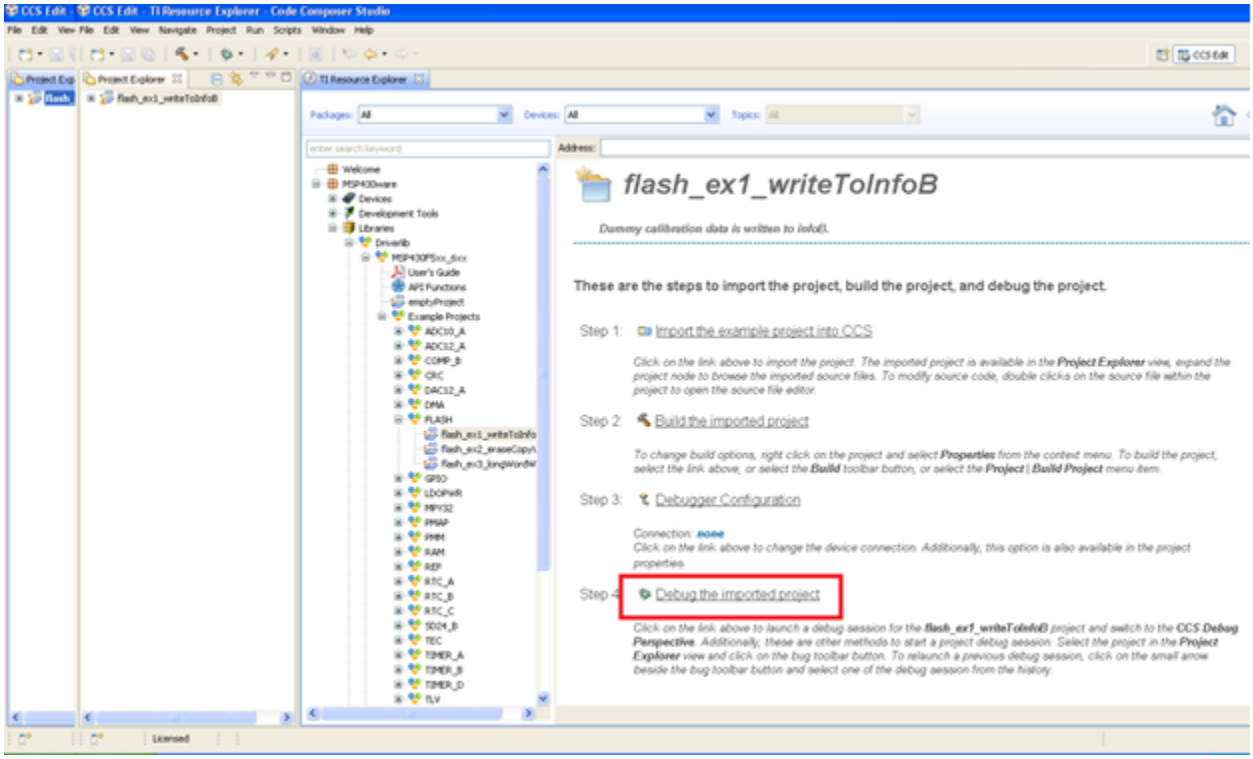
Driverlib is designed per Family. If a common device family userŠs guide exists for a group of devices, these devices belong to the same ŚfamilyŠ. Currently driverlib is available for the following family of devices. MSP430F5xx_6xx MSP430FR57xx MSP430FR5xx_6xx



Click on the MSP430F5xx_6xx to navigate to the driverlib based example code for that family.

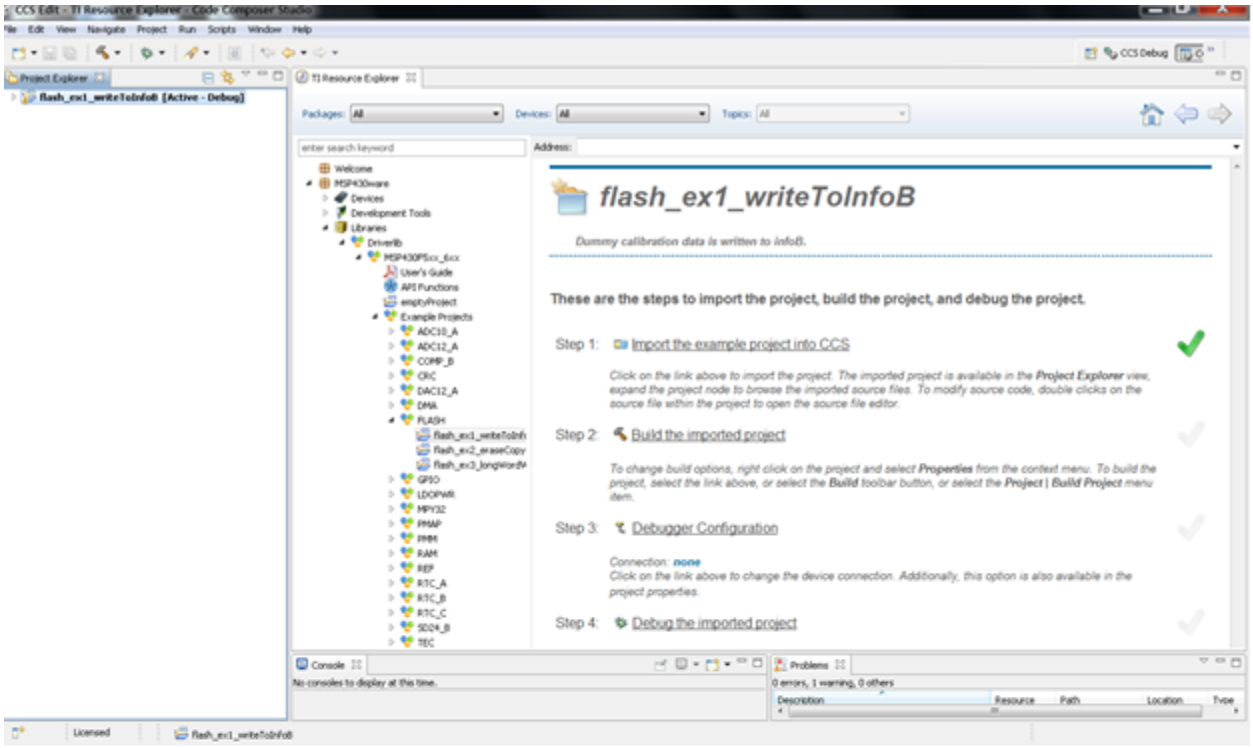


The various peripherals are listed in alphabetical order. The names of peripherals are as in device family userŠs guide. Clicking on a peripheral name lists the driverlib example code for that peripheral. The screenshot below shows an example when the user clicks on GPIO peripheral.

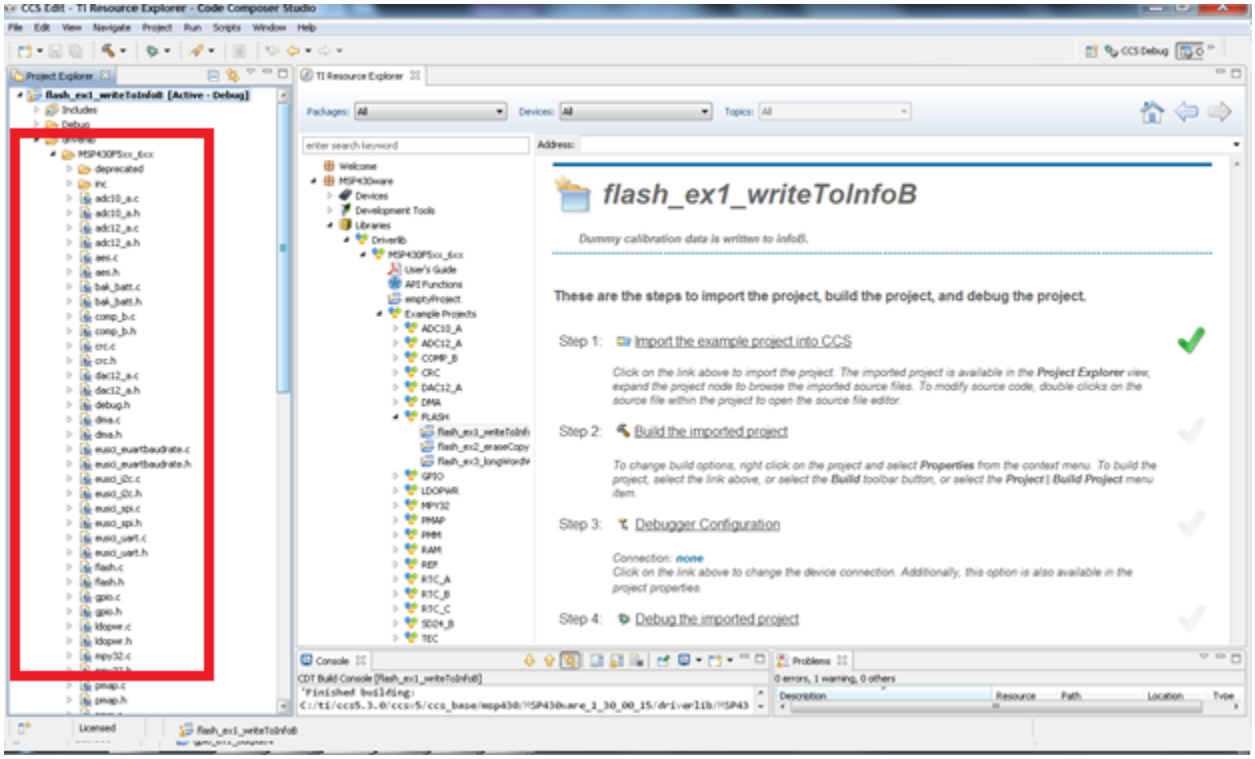

flash_ex1_writeToInfoB
Dummy calibration data is written to Info0.
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

Now click on the specific example you are interested in. On the right side there are options to Import/Build/Download and

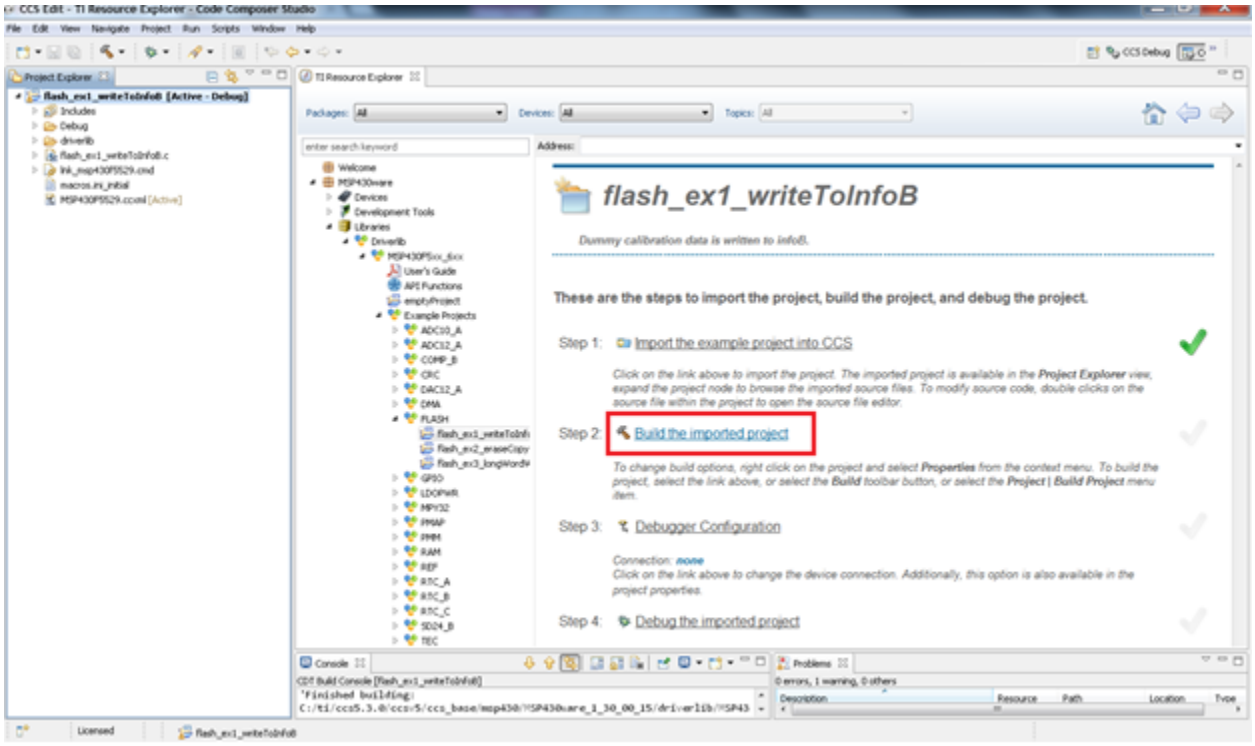
Debug. Import the project by clicking on the ŞImport the example project into CCSŤ


flash_ex1_writeToInfoB
Dummy calibration data is written to infoB.
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

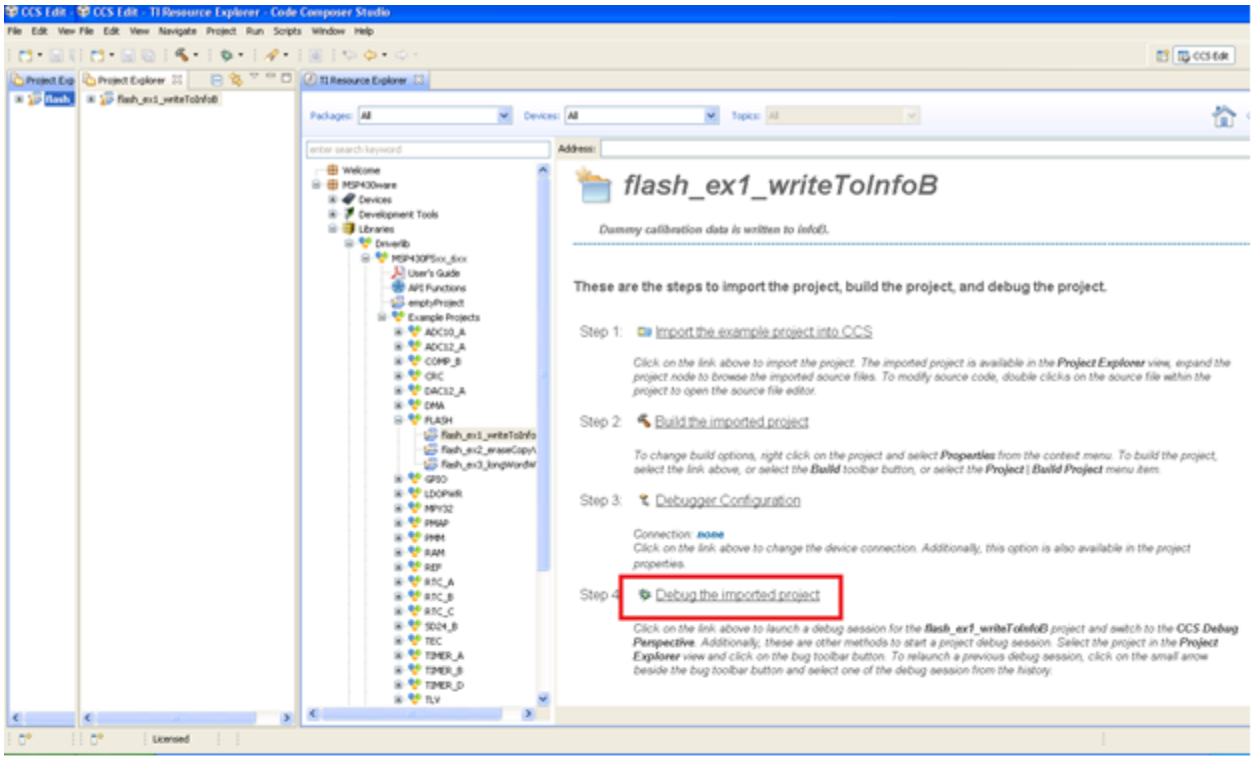
The imported project can be viewed on the left in the Project Explorer. All required driverlib source and header files are included inside the driverlib folder. All driverlib source and header files are linked to the example projects. So if the user modifies any of these source or header files, the original copy of the installed MSP430ware driverlib source and header files get modified.


flash_ex1_writeToInfoB
Dummy calibration data is written to InfoB.
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

Now click on Build the imported project on the right to build the example project.

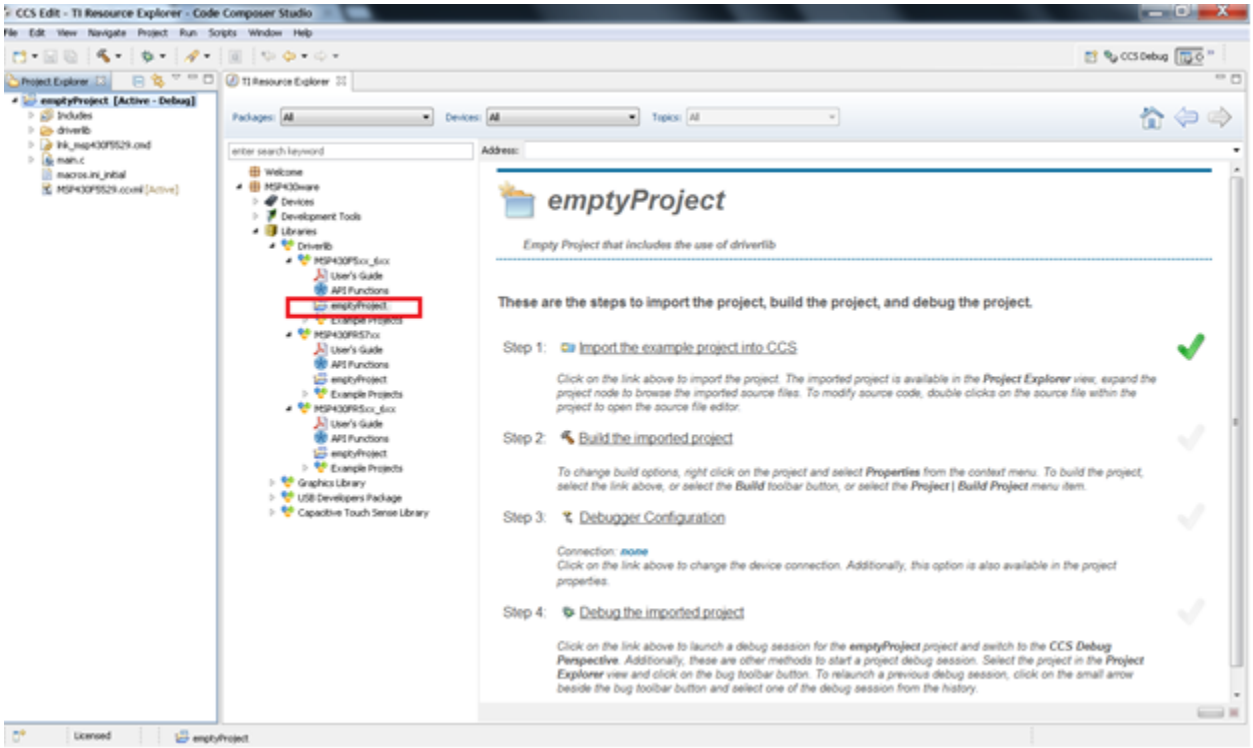

flash_ex1_writeToInfoB
Dummy calibration data is written to infoB.
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

Now click on Build the imported project on the right to build the example project.


flash_ex1_writeToInfoB
Dummy calibration data is written to Info0.
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

The COM port to download to can be changed using the Debugger Configuration option on the right if required.

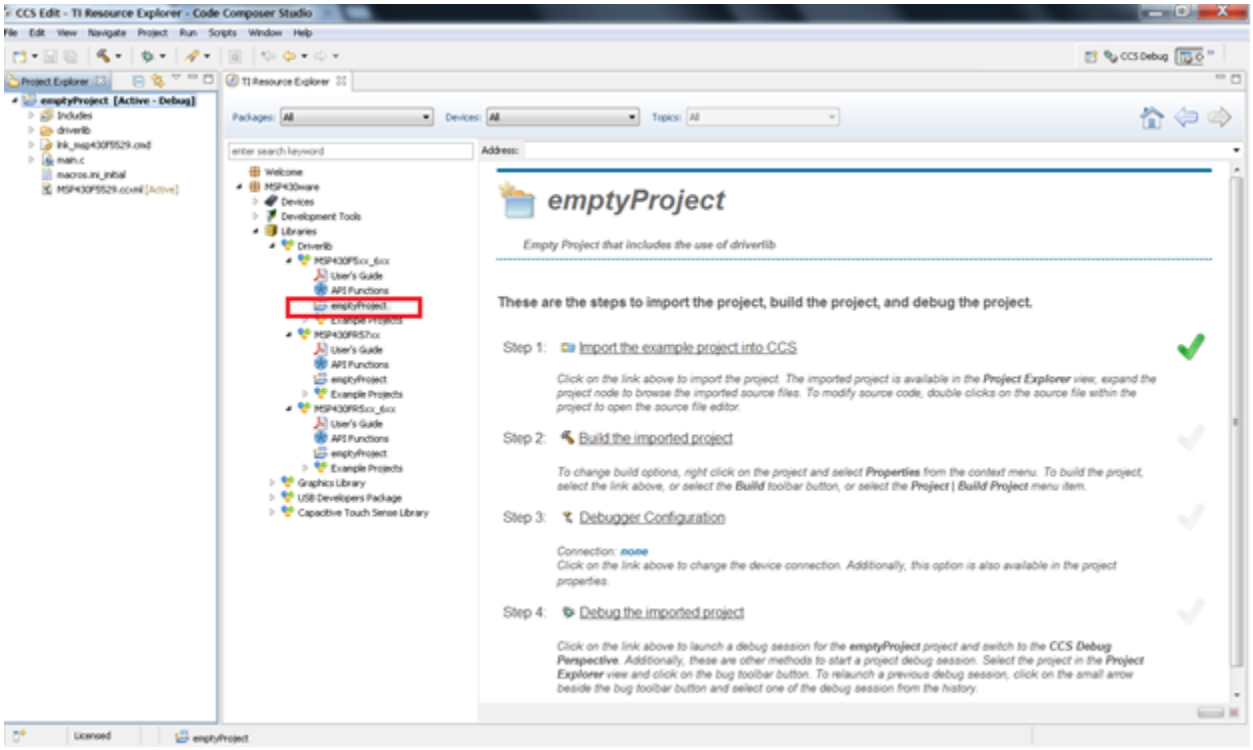
To get started on a new project we recommend getting started on an empty project we provide. This project has all the driverlib source files, header files, project paths are set by default.


CCS Edit - TI Resource Explorer - Code Composer Studio
emptyProject
Empty Project that includes the use of driverlib
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

The main.c included with the empty project can be modified to include user code.

3 How to create a new user project that uses Driverlib

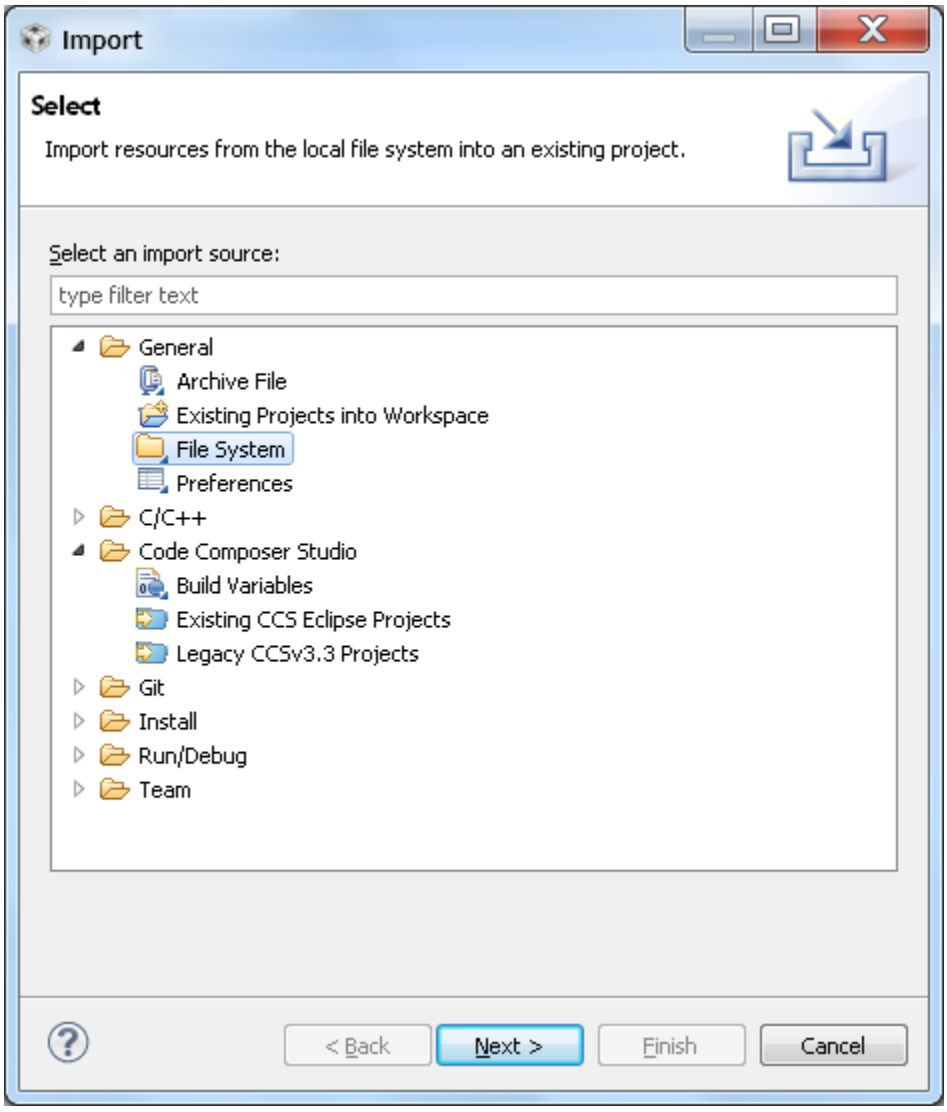
To get started on a new project we recommend getting started on an empty project we provide. This project has all the driverlib source files, header files, project paths are set by default.


CCS Edit - TI Resource Explorer - Code Composer Studio
emptyProject
Empty Project that includes the use of driverlib
These are the steps to import the project, build the project, and debug the project.
Step 1: Import the example project into CCS
Step 2: Build the imported project
Step 3: Debugger Configuration
Step 4: Debug the imported project

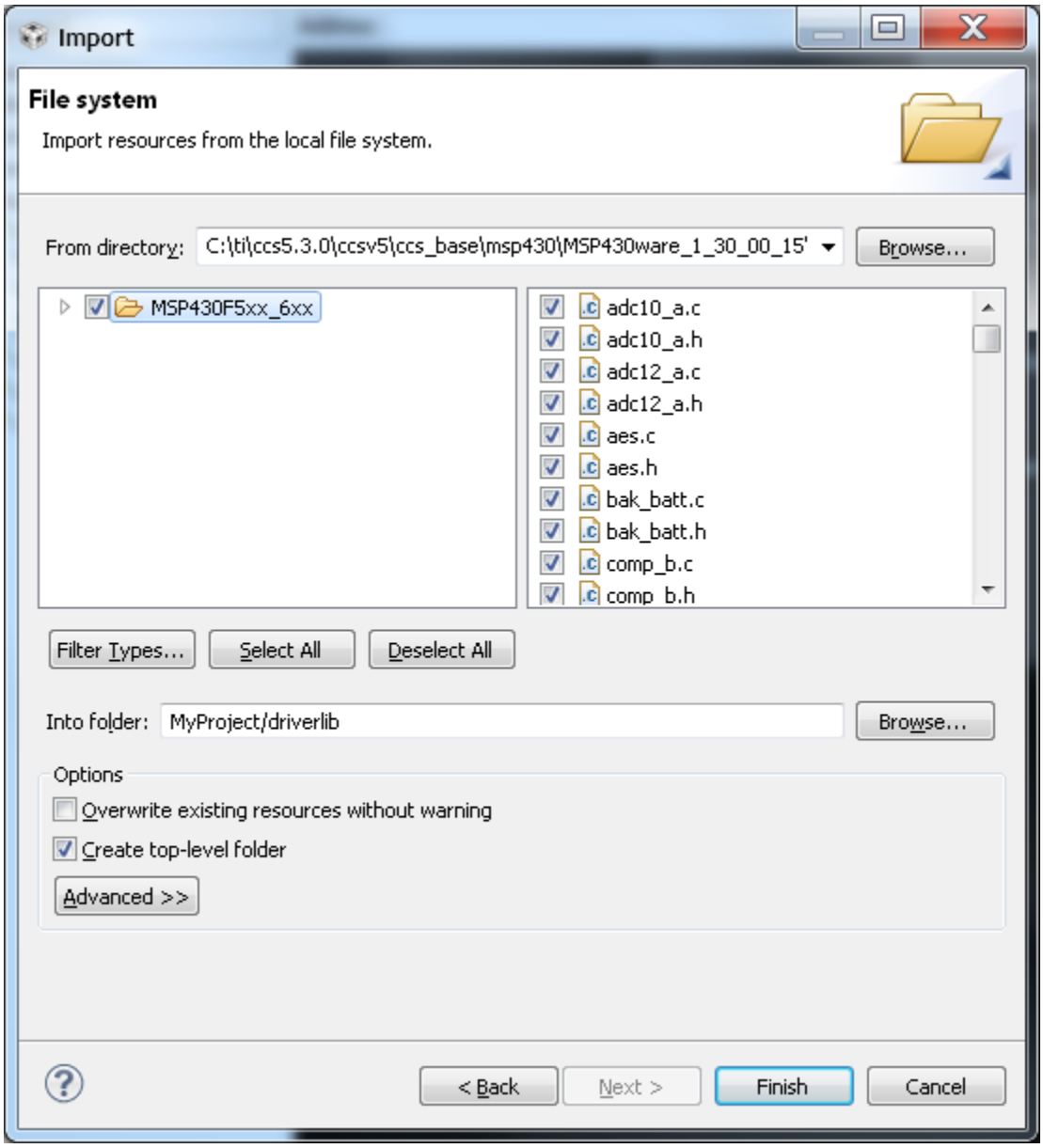
The main.c included with the empty project can be modified to include user code.

4 How to include driverlib into your existing project

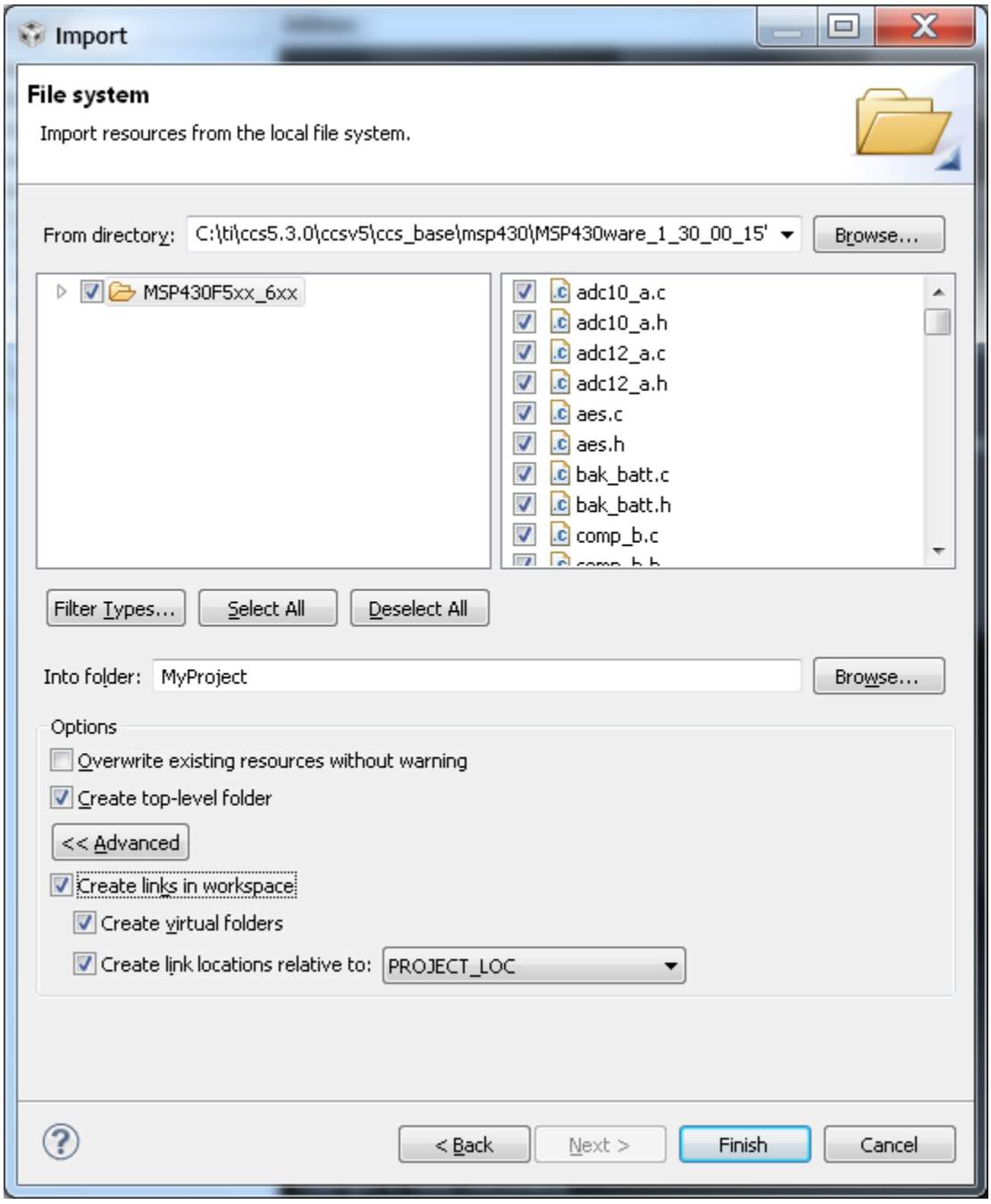
STEP 1 Create a subfolder MyProject->driverlib Import the family folder from the installed ŞMSP430ware driverlibŤ by choosing Import->general->File system as shown in the screenshot below . C:.3.0



Make sure you check the ŞCreate top-level folderŤ checkbox. This ensures that a top level folder with the family name is created withing driverlib sub-folder. A local copy of the driverlib source and header files are created within the project and are included in the project when the filesystem is imported this way. Any change made to the driverlib source or header files reflects only in the local copy and not in the original installed version of the MSP430ware driverlib source/header files.



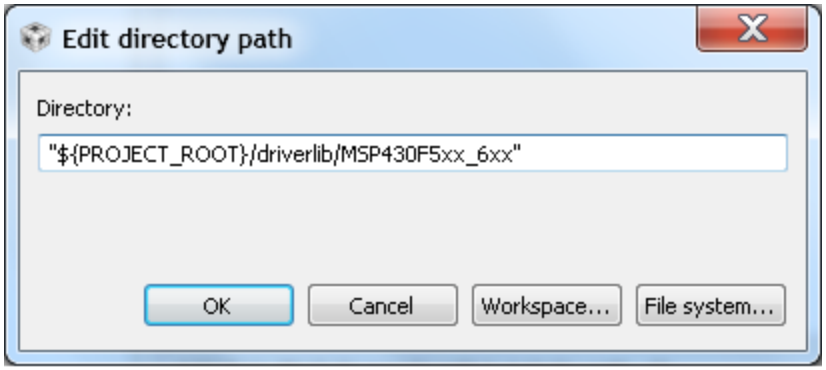
If the user prefers to create a link to the original MSP430ware driverlib source/header files, then before clicking finish, click on Advanced->Create links in workspace. Also pick how the files should be linked from the options in the ŞCreate link locations relative to Şcombo box



STEP 2

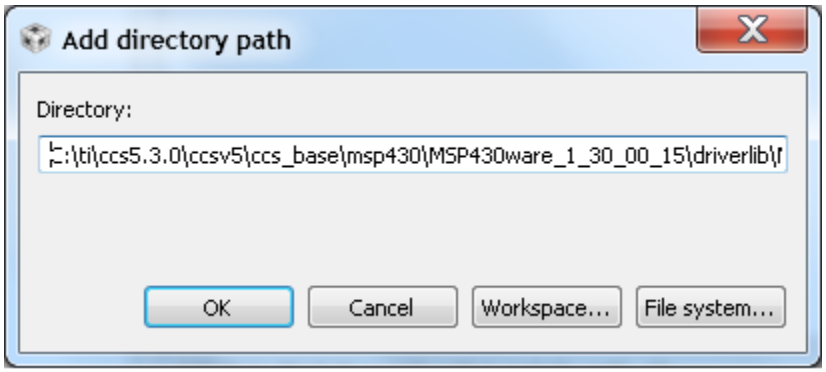
In the project setting include the path of the driverlib source/header files.

If the driverlib files are copied into project Ű Include the following path



If the driverlib files are linked into project Ű Include the MSP430ware driverlib install path to the include paths

In this example "C:\ti\ccs5.3.0\ccsv5\ccs_base\msp430\MSP430ware_1_30_00_15\driverlib\MSP430FR5xx_6xx"



STEP 3

In the source files that use driverlib API calls

include Şinc/hw_memmap.hŤ instead of including msp430.h

STEP 4

To use driverlib APIs to configure/use any peripheral, include the corresponding header file in the user file.

For example if you would like to use WDT_A_hold() API, use include Şwdt_a.hŤ

5 10-Bit Analog-to-Digital Converter (ADC10_A)

Introduction 23
API Functions 23
Programming Example 24

5.1 Introduction

The 10-Bit Analog-to-Digital (ADC10_A) API provides a set of functions for using the MSP430Ware ADC10_A modules. Functions are provided to initializae the ADC10_A modules, setup signal sources and reference voltages, and manage interrupts for the ADC10_A modules.

The ADC10_A module provides the ability to convert analog signals into a digital value in respect to given reference voltages. The ADC10_A can generate digital values from 0 to Vcc with an 8- or 10-bit resolution. It operates in 2 different sampling modes, and 4 different conversion modes. The smapling modes are extended sampling and pulse sampling, in extended sampling the sample/hold signal must stay high for the duration of sampling, while in pulse mode a sampling timer is setup to start on a rising edge of the sample/hold signal and sample for a specified amount of clock cycles. The 4 conversion modes are single-channel single conversion, sequence of channels single-conversion, repeated single channel conversions, and repeated sequence of channels conversions.

The ADC10_A module can generate multiple interrupts. An interrupt can be asserted when a conversion is complete, when a conversion is about to overwrite the converted data in the memory buffer before it has been read out, and/or when a conversion is about to start before the last conversion is complete. The ADC10_A also has a window comparator feature which asserts interrupts when the input signal is above a high threshold, below a low threshold, or between the two at any given moment.

This driver is contained in `adc10_a.c`, with `adc10_a.h` containing the API definitions for use by applications.

5.2 API Functions

The ADC10_A API is broken into three groups of functions: those that deal with initialization and conversions, those that handle interrupts, and those that handle auxillary features of the ADC10_A.

The ADC10_A initialization and conversion functions are

- ADC10_A_init
- ADC10_A_memoryConfigure
- ADC10_A_setupSamplingTimer
- ADC10_A_disableSamplingTimer
- ADC10_A_setWindowComp
- ADC10_A_startConversion
- ADC10_A_disableConversions
- ADC10_A_getResults
- ADC10_A_isBusy

The ADC10_A interrupts are handled by

- ADC10_A_enableInterrupt
- ADC10_A_disableInterrupt
- ADC10_A_clearInterrupt
- ADC10_A_getInterruptStatus

Auxilary features of the ADC10_A are handled by

- ADC10_A_setResolution
- ADC10_A_setSampleHoldSignalInversion
- ADC10_A_setDataReadBackFormat
- ADC10_A_enableReferenceBurst
- ADC10_A_disableReferenceBurst
- ADC10_A_setReferenceBufferSamplingRate
- ADC10_A_getMemoryAddressForDMA
- ADC10_A_enable
- ADC10_A_disable

5.3 Programming Example

The following example shows how to initialize and use the ADC10_A API to start a single channel, single conversion.

```
    // Initialize ADC10_A with ADC10_A's built-in oscillator
    ADC10_A_init (ADC10_A_BASE,
                          ADC10_A_SAMPLEHOLDSOURCE_SC,
                          ADC10_A_CLOCKSOURCE_ADC10_AOSC,
                          ADC10_A_CLOCKDIVIDEBY_1);

    //Switch ON ADC10_A
ADC10_A_enable(ADC10_A_BASE);

    // Setup sampling timer to sample-and-hold for 16 clock cycles
    ADC10_A_setupSamplingTimer (ADC10_A_BASE,
                                                    ADC10_A_CYCLEHOLD_16_CYCLES,
                                                    FALSE);

    // Configure the Input to the Memory Buffer with the specified Reference Voltages
    ADC10_A_memoryConfigure (ADC10_A_BASE,
                                                ADC10_A_INPUT_A0,
                                                ADC10_A_VREF_AVCC, // Vref+ = AVcc
                                                ADC10_A_VREF_AVSS  // Vref- = AVss
                                                );
    while (1)
    {
            // Start a single conversion, no repeating or sequences.
            ADC10_A_startConversion (ADC10_A_BASE,
                                                     ADC10_A_SINGLECHANNEL);

            // Wait for the Interrupt Flag to assert
            while( !(ADC10_A_getInterruptStatus(ADC10_A_BASE,ADC10_AIFG0)) );

            // Clear the Interrupt Flag and start another conversion
            ADC10_A_clearInterrupt(ADC10_A_BASE,ADC10_AIFG0);
    }
```

6 12-Bit Analog-to-Digital Converter (ADC12)

Introduction 25
API Functions 25
Programming Example 26

6.1 Introduction

The 12-Bit Analog-to-Digital (ADC12_A) API provides a set of functions for using the MSP430Ware ADC12_A modules. Functions are provided to initializae the ADC12_A modules, setup signal sources and reference voltages for each memory buffer, and manage interrupts for the ADC12_A modules.

The ADC12_A module provides the ability to convert analog signals into a digital value in respect to given reference voltages. The ADC12_A can generate digital values from 0 to Vcc with an 8-, 10- or 12-bit resolution, with 16 different memory buffers to store conversion results. It operates in 2 different sampling modes, and 4 different conversion modes. The sampling modes are extended sampling and pulse sampling, in extended sampling the sample/hold signal must stay high for the duration of sampling, while in pulse mode a sampling timer is setup to start on a rising edge of the sample/hold signal and sample for a specified amount of clock cycles. The 4 conversion modes are single-channel single conversion, sequence of channels single-conversion, repeated single channel conversions, and repeated sequence of channels conversions.

The ADC12_A module can generate multiple interrupts. An interrupt can be asserted for each memory buffer when a conversion is complete, or when a conversion is about to overwrite the converted data in any of the memory buffers before it has been read out, and/or when a conversion is about to start before the last conversion is complete.

This driver is contained in `adc12_a.c`, with `adc12_a.h` containing the API definitions for use by applications.

6.2 API Functions

The ADC12 API is broken into three groups of functions: those that deal with initialization and conversions, those that handle interrupts, and those that handle auxillary features of the ADC12.

The ADC12 initialization and conversion functions are

- ADC12_A_init
- ADC12_A_memoryConfigure
- ADC12_A_setupSamplingTimer
- ADC12_A_disableSamplingTimer
- ADC12_A_startConversion
- ADC12_A_disableConversions
- ADC12_A_readResults
- ADC12_A_isBusy

The ADC12 interrupts are handled by

- ADC12_A_enableInterrupt
- ADC12_A_disableInterrupt
- ADC12_A_clearInterrupt
- ADC12_A_getInterruptStatus

Auxilary features of the ADC12 are handled by

- ADC12_A_setResolution
- ADC12_A_setSampleHoldSignalInversion
- ADC12_A_setDataReadBackFormat
- ADC12_A_enableReferenceBurst
- ADC12_A_disableReferenceBurst
- ADC12_A_setReferenceBufferSamplingRate
- ADC12_A_getMemoryAddressForDMA
- ADC12_A_enable
- ADC12_A_disable

6.3 Programming Example

The following example shows how to initialize and use the ADC12 API to start a single channel, single conversion.

```
    // Initialize ADC12 with ADC12's built-in oscillator
    ADC12_A_init (ADC12_A_BASE,
                          ADC12_A_SAMPLEHOLDSOURCE_SC,
                          ADC12_A_CLOCKSOURCE_ADC12OSC,
                          ADC12_A_CLOCKDIVIDEBY_1);

//Switch ON ADC12
ADC12_A_enable(ADC12_A_BASE);

    // Setup sampling timer to sample-and-hold for 16 clock cycles
    ADC12_A_setupSamplingTimer (ADC12_A_BASE,
                                                    ADC12_A_CYCLEHOLD_64_CYCLES,
                                                    ADC12_A_CYCLEHOLD_4_CYCLES,
                                                    FALSE);

    // Configure the Input to the Memory Buffer with the specified Reference Voltages
    ADC12_A_memoryConfigure (ADC12_A_BASE,
                         ADC12_A_MEMORY_0,
                                              ADC12_A_INPUT_A0,
                                              ADC12_A_VREF_AVCC, // Vref+ = AVcc
                                              ADC12_A_VREF_AVSS, // Vref- = AVss
                                              FALSE
                                              );
    while (1)
    {
            // Start a single conversion, no repeating or sequences.
            ADC12_A_startConversion (ADC12_A_BASE,
                                 ADC12_A_MEMORY_0,
                                                    ADC12_A_SINGLECHANNEL);

            // Wait for the Interrupt Flag to assert
            while( !(ADC12_A_getInterruptStatus(ADC12_A_BASE,ADC12IFG0)) );
```

```
        // Clear the Interrupt Flag and start another conversion
        ADC12_A_clearInterrupt(ADC12_A_BASE,ADC12IFG0);
}
```

7 Advanced Encryption Standard (AES)

Introduction 29
API Functions 29
Programming Example 30

7.1 Introduction

The AES accelerator module performs encryption and decryption of 128-bit data with 128-bit keys according to the advanced encryption standard (AES) (FIPS PUB 197) in hardware. The AES accelerator features are:

- Encryption and decryption according to AES FIPS PUB 197 with 128-bit key
- On-the-fly key expansion for encryption and decryption
- Off-line key generation for decryption
- Byte and word access to key, input, and output data
- AES ready interrupt flag The AES256 accelerator module performs encryption and decryption of 128-bit data with 128-/192-/256-bit keys according to the advanced encryption standard (AES) (FIPS PUB 197) in hardware. The AES accelerator features are: AES encryption Ű 128 bit - 168 cycles Ű 192 bit - 204 cycles Ű 256 bit - 234 cycles AES decryption Ű 128 bit - 168 cycles Ű 192 bit - 206 cycles Ű 256 bit - 234 cycles
- On-the-fly key expansion for encryption and decryption
- Offline key generation for decryption
- Shadow register storing the initial key for all key lengths
- Byte and word access to key, input data, and output data
- AES ready interrupt flag

This driver is contained in `aes.c`, with `aes.h` containing the API definitions for use by applications.

7.2 API Functions

The AES module APIs are

- AES_setCipherKey(),
- AES_encryptData(),
- AES_decryptDataUsingEncryptionKey(),
- AES_generateFirstRoundKey(),
- AES_decryptData(),
- AES_reset(),
- AES_startEncryptData(),
- AES_startDecryptDataUsingEncryptionKey(),

- AES_startDecryptData(),
- AES_startGenerateFirstRoundKey(),
- AES_getDataOut()

The AES interrupt handler functions

- AES_enableInterrupt(),
- AES_disableInterrupt(),
- AES_clearInterruptFlag(),

7.3 Programming Example

The following example shows some AES operations using the APIs

```
unsigned char Data[16] =                {       0x30, 0x31, 0x32, 0x33,
                                                                        0x34, 0x35, 0x36, 0x37,
                                                                        0x38, 0x39, 0x0A, 0x0B,
                                                                        0x0C, 0x0D, 0x0E, 0x0F
unsigned char CipherKey[16] =   {       0xAA, 0xBB, 0x02, 0x03,
                                                                        0x04, 0x05, 0x06, 0x07,
                                                                        0x08, 0x09, 0x0A, 0x0B,
                                                                        0x0C, 0x0D, 0x0E, 0x0F
unsigned char DataAES[16];              // Encrypted data
unsigned char DataunAES[16];    // Decrypted data

// Load a cipher key to module
AES_setCipherKey(AES_BASE, CipherKey);

// Encrypt data with preloaded cipher key
AES_encryptData(AES_BASE, Data, DataAES);

// Decrypt data with keys that were generated during encryption - takes 214 MCLK
// This function will generate all round keys needed for decryption first and then
// the encryption process starts
AES_decryptDataUsingEncryptionKey(AES_BASE, DataAES, DataunAES);
```

8 Battery Backup System

Introduction 31
API Functions 31
Programming Example 31

8.1 Introduction

The Battery Backup System (BATBCK) API provides a set of functions for using the MSP430Ware BATBCK modules. Functions are provided to handle the backup Battery sub-system, initialize and enable the backup Battery charger, and control acces to and from the backup RAM space.

The BATBCK module offers no interrupt, and is used only to control the Battery backup sub-system, Battery charger, and backup RAM space.

This driver is contained in `batbck.c`, with `batbck.h` containing the API definitions for use by applications.

8.2 API Functions

The BATBCK API is divided into three groups: one that handles the Battery backup sub-system, one that controls the charger, and one that controls access to and from the backup RAM space.

The BATBCK sub-system controls are handled by

- BAK_BATT_unlockBackupSubSystem
- BAK_BATT_enableBackupSupplyToADC
- BAK_BATT_disableBackupSupplyToADC
- BAK_BATT_manuallySwitchToBackupSupply
- BAK_BATT_disable

The BATBCK charger is controlled by

- BAK_BATT_chargerInitAndEnable
- BAK_BATT_disableCharger

The backup RAM space is accessed by

- BAK_BATT_setBackupRAMData
- BAK_BATT_getBackupRAMData

8.3 Programming Example

9 Comparator (COMP_B)

Introduction 33
API Functions 33
Programming Example 34

9.1 Introduction

The Comparator B (COMP_B) API provides a set of functions for using the MSP430Ware COMP_B modules. Functions are provided to initialize the COMP_B modules, setup reference voltages for input, and manage interrupts for the COMP_B modules.

The COMP_B module provides the ability to compare two analog signals and use the output in software and on an output pin. The output represents whether the signal on the positive terminal is higher than the signal on the negative terminal. The COMP_B may be used to generate a hysteresis. There are 16 different inputs that can be used, as well as the ability to short 2 input together. The COMP_B module also has control over the REF module to generate a reference voltage as an input.

The COMP_B module can generate multiple interrupts. An interrupt may be asserted for the output, with seperate interrupts on whether the output rises, or falls.

This driver is contained in `comp_b.c`, with `comp_b.h` containing the API definitions for use by applications.

9.2 API Functions

The COMP_B API is broken into three groups of functions: those that deal with initialization and output, those that handle interrupts, and those that handle auxillary features of the COMP_B.

The COMP_B initialization and output functions are

- COMP_B_init
- COMP_B_setReferenceVoltage
- COMP_B_enable
- COMP_B_disable
- COMP_B_outputValue

The COMP_B interrupts are handled by

- COMP_B_enableInterrupt
- COMP_B_disableInterrupt
- COMP_B_clearInterrupt
- COMP_B_getInterruptStatus
- COMP_B_interruptSetEdgeDirection
- COMP_B_interruptToggleEdgeDirection

Auxilary features of the COMP_B are handled by

- COMP_B_enableShortOfInputs
- COMP_B_disableShortOfInputs
- COMP_B_disableInputBuffer
- COMP_B_enableInputBuffer
- COMP_B_IOSwap

9.3 Programming Example

The following example shows how to initialize and use the COMP_B API to turn on an LED when the input to the positive terminal is highed than the input to the negative terminal.

```
// Initialize the Comparator B module
/* Base Address of Comparator B,
  Pin CB0 to Positive(+) Terminal,
  Reference Voltage to Negative(-) Terminal,
  Normal Power Mode,
  Output Filter On with minimal delay,
  Non-Inverted Output Polarity
*/
COMP_B_init(COMP_B_BASE,
          COMP_B_INPUT0,
          COMP_B_VREF,
          COMP_B_POWERMODE_NORMALMODE,
          COMP_B_FILTEROUTPUT_DLYLVL1,
          COMP_B_NORMALOUTPUTPOLARITY
          );

// Set the reference voltage that is being supplied to the (-) terminal
/* Base Address of Comparator B,
 Reference Voltage of 2.0 V,
 Upper Limit of 2.0*(32/32) = 2.0V,
 Lower Limit of 2.0*(32/32) = 2.0V
*/
COMP_B_setReferenceVoltage(COMP_B_BASE,
                           COMP_B_VREFBASE2_5V,
                           32,
                           32
                           );

// Allow power to Comparator module
COMP_B_enable(COMP_B_BASE);

// delay for the reference to settle
__delay_cycles(75);
```

10 Cyclical Redundancy Check (CRC)

Introduction 35
API Functions 35
Programming Example 35

10.1 Introduction

The Cyclic Redundancy Check (CRC) API provides a set of functions for using the MSP430Ware CRC module. Functions are provided to initialize the CRC and create a CRC signature to check the validity of data. This is mostly useful in the communication of data, or as a startup procedure to as a more complex and accurate check of data.

The CRC module offers no interrupts and is used only to generate CRC signatures to verify against pre-made CRC signatures (Checksums).

This driver is contained in `crc.c`, with `crc.h` containing the API definitions for use by applications.

10.2 API Functions

The CRC API is one group that controls the CRC module.

- CRC_setSeed
- CRC_setDataByte
- CRC_setDataWord
- CRC_setSignatureByteReversed
- CRC_getSignature
- CRC_getResult
- CRC_getResultBitReversed

10.3 Programming Example

The following example shows how to initialize and use the CRC API to generate a CRC signature on an array of data that can be included in a UART message with the data to check for validity.

```
unsigned int crcSeed = 0xBEEF;
unsigned int data[] = {0x0123,
                       0x4567,
                       0x8910,
                       0x1112,
                       0x1314};
unsigned int crcResult;
int i;

// Stop WDT
```

```
WDT_hold(WDT_A_BASE);

// Set P1.0 as an output
GPIO_setAsOutputPin(GPIO_PORT_P1,
                    GPIO_PIN0);

// Set the CRC seed
CRC_setSeed(CRC_BASE,
            crcSeed);

for(i=0; i<5; i++)
{
  // Add all of the values into the CRC signature
  CRC_setDataWord(CRC_BASE,
                  data[i]);
}

// Save the current CRC signature checksum to be compared for later
crcResult = CRC_getResult(CRC_BASE);
```

11 12-bit Digital-to-Analog Converter (DAC12_A)

Introduction 37
API Functions 37
Programming Example 38

11.1 Introduction

The 12-Bit Digital-to-Analog (DAC12_A) API provides a set of functions for using the MSP430Ware DAC12_A modules. Functions are [rpvided to initialize setup the DAC12_A modules, calibrate the output signal, and manage the interrupts for the DAC12_A modules.

The DAC12_A module provides the ability to convert digital values into an analog signal for output to a pin. The DAC12_A can generate signals from 0 to Vcc from an 8- or 12-bit value. There can be one or two DAC12_A modules in a device, and if there are two they can be grouped together to create two analog signals in simultaneously. There are 3 ways to latch data in to the DAC module, and those are by software with the startConversion API function call, as well as by the Timer A output of CCR1 or Timer B output of CCR2.

The calibration API will unlock and start calibration, then wait for the calibration to end before locking it back up, all in one API. There are also functions to read out the calibration data, as well as be able to set it manually.

The DAC12_A module can generate one interrupt for each DAC module. It will generate the interrupt when the data has been latched into the DAC module to be output into an analog signal.

This driver is contained in `dac12_a.c`, with `dac12_a.h` containing the API definitions for use by applications.

11.2 API Functions

The DAC12_A API is broken into three groups of functions: those that deal with initialization and conversions, those that deal with calibration of the output, and those that handle interrupts.

The DAC12_A initialization and conversion functions are

- DAC12_A_init
- DAC12_A_setAmplifierSetting
- DAC12_A_disable
- DAC12_A_enableGrouping
- DAC12_A_disableGrouping
- DAC12_A_enableConversions
- DAC12_A_setData
- DAC12_A_disableConversions
- DAC12_A_setResolution

- DAC12_A_setInputDataFormat
- DAC12_A_getDataBufferMemoryAddressForDMA

Calibration features of the DAC12_A are handled by

- DAC12_A_calibrateOutput
- DAC12_A_getCalibrationData
- DAC12_A_setCalibrationOffset

The DAC12_A interrupts are handled by

- DAC12_A_enableInterrupt
- DAC12_A_disableInterrupt
- DAC12_A_getInterruptStatus
- DAC12_A_clearInterrupt

11.3 Programming Example

The following example shows how to initialize and use the DAC12_A API to output a 1.5V analog signal.

```
DAC12_A_init (DAC12_A_BASE,
            DAC12_A_SUBMODULE_0,            // Initialize DAC12_A_0
            DAC12_A_OUTPUT_1,               // Choose P6.6 as output
            DAC12_A_VREF_AVCC,              // Use AVcc as Vref+
            DAC12_A_VREFx1,                 // Multiply Vout by 1
            DAC12_A_AMP_MEDIN_MEDOUT,       // Use medium settling speed/current
            DAC12_A_TRIGGER_ENCBYPASS       // Auto trigger as soon as data is set
            );

// Calibrate output buffer for DAC12_A_0
DAC12_A_calibrateOutput(DAC12_A_BASE,
                        DAC12_A_SUBMODULE_0);

DAC12_A_setData(DAC12_A_BASE,
              DAC12_A_SUBMODULE_0,          // Set 0x7FF (~1.5V)
              0x7FF                        // into data buffer for DAC12_A_0
              );
```

12 Direct Memory Access (DMA)

Introduction 39
API Functions 39
Programming Example 40

12.1 Introduction

The Direct Memory Access (DMA) API provides a set of functions for using the MSP430Ware DMA modules. Functions are provided to initialize and setup each DMA channel with the source and destination addresses, manage the interrupts for each channel, and set bits that affect all DMA channels.

The DMA module provides the ability to move data from one address in the device to another, and that includes other peripheral addresses to RAM or vice-versa, all without the actual use of the CPU. Please be advised, that the DMA module does halt the CPU for 2 cycles while transfering, but does not have to edit any registers or anything. The DMA can transfer by bytes or words at a time, and will automatically increment or decrement the source or destination address if desired. There are also 6 different modes to transfer by, including single-transfer, block-transfer, and burst-block-transfer, as well as repeated versions of those three different kinds which allows transfers to be repeated without having re-enable transfers.

The DMA settings that affect all DMA channels include prioritization, from a fixed priority to dynamic round-robin priority. Another setting that can be changed is when transfers occur, the CPU may be in a read-modify-write operation which can be disasterous to time sensitive material, so this can be disabled. And Non-Maskable-Interrupts can indeed be maskable to the DMA module if not enabled.

The DMA module can generate one interrupt per channel. The interrupt is only asserted when the specified amount of transfers has been completed. With single-transfer, this occurs when that many single transfers have occured, while with block or burst-block transfers, once the block is completely transfered the interrupt is asserted.

12.2 API Functions

The DMA API is broken into three groups of functions: those that deal with initialization and transfers, those that handle interrupts, and those that affect all DMA channels.

The DMA initialization and transfer functions are: DMA_init DMA_setSrcAddress DMA_setDstAddress DMA_enableTransfers DMA_disableTransfers DMA_startTransfer DMA_setTransferSize

The DMA interrupts are handled by: DMA_enableInterrupt DMA_disableInterrupt DMA_getInterruptStatus DMA_clearInterrupt DMA_NMIAbortStatus DMA_clearNMIAbort

Features of the DMA that affect all channels are handled by: DMA_disableTransferDuringReadModifyWrite DMA_enableTransferDuringReadModifyWrite DMA_enableRoundRobinPriority DMA_disableRoundRobinPriority DMA_enableNMIAbort DMA_disableNMIAbort

12.3 Programming Example

The following example shows how to initialize and use the DMA API to transfer words from one spot in RAM to another.

```
 // Initialize and Setup DMA Channel 0
 /*
Base Address of the DMA Module
Configure DMA channel 0
Configure channel for repeated block transfers
DMA interrupt flag will be set after every 16 transfers
Use DMA_startTransfer() function to trigger transfers
Transfer Word-to-Word
Trigger upon Rising Edge of Trigger Source Signal
  */
 DMA_init(DMA_BASE,
          DMA_CHANNEL_0,
          DMA_TRANSFER_REPEATED_BLOCK,
          16,
          DMA_TRIGGERSOURCE_0,
          DMA_SIZE_SRCWORD_DSTWORD,
          DMA_TRIGGER_RISINGEDGE);
 /*
Base Address of the DMA Module
Configure DMA channel 0
Use 0x1C00 as source
Increment source address after every transfer
  */
 DMA_setSrcAddress(DMA_BASE,
                   DMA_CHANNEL_0,
                   0x1C00,
                   DMA_DIRECTION_INCREMENT);
 /*
Base Address of the DMA Module
Configure DMA channel 0
Use 0x1C20 as destination
Increment destination address after every transfer
  */
 DMA_setDstAddress(DMA_BASE,
                   DMA_CHANNEL_0,
                   0x1C20,
                   DMA_DIRECTION_INCREMENT);

 // Enable transfers on DMA channel 0
 DMA_enableTransfers(DMA_BASE,
                     DMA_CHANNEL_0);

 while(1)
 {
   // Start block tranfer on DMA channel 0
   DMA_startTransfer(DMA_BASE,
                     DMA_CHANNEL_0);
 }
```

13 EUSCI Universal Asynchronous Receiver/Transmitter (EUSCI_A_UART)

Introduction 41
API Functions 41
Programming Example 42

13.1 Introduction

The MSP430Ware library for UART mode features include:

- Odd, even, or non-parity
- Independent transmit and receive shift registers
- Separate transmit and receive buffer registers
- LSB-first or MSB-first data transmit and receive
- Built-in idle-line and address-bit communication protocols for multiprocessor systems
- Receiver start-edge detection for auto wake up from LPMx modes
- Status flags for error detection and suppression
- Status flags for address detection
- Independent interrupt capability for receive and transmit

In UART mode, the USCI transmits and receives characters at a bit rate asynchronous to another device. Timing for each character is based on the selected baud rate of the USCI. The transmit and receive functions use the same baud-rate frequency.

This driver is contained in `eusci_a_uart.c`, with `eusci_a_uart.h` containing the API definitions for use by applications.

13.2 API Functions

The EUSI_A_UART API provides the set of functions required to implement an interrupt driven EUSI_A_UART driver. The EUSI_A_UART initialization with the various modes and features is done by the EUSCI_A_UART_init(). At the end of this fucntion EUSI_A_UART is initialized and stays disabled. EUSCI_A_UART_enable() enables the EUSI_A_UART and the module is now ready for transmit and receive. It is recommended to iniailize the EUSI_A_UART via EUSCI_A_UART_init(), enable the required interrupts and then enable EUSI_A_UART via EUSCI_A_UART_enable().

The EUSI_A_UART API is broken into three groups of functions: those that deal with configuration and control of the EUSI_A_UART modules, those used to send and receive data, and those that deal with interrupt handling and those dealing with DMA.

Configuration and control of the EUSI_UART are handled by the

- EUSCI_A_UART_init()

- EUSCI_A_UART_initAdvance()
- EUSCI_A_UART_enable()
- EUSCI_A_UART_disable()
- EUSCI_A_UART_setDormant()
- EUSCI_A_UART_resetDormant()
- EUSCI_A_UART_selectDeglitchTime()

Sending and receiving data via the EUSI_UART is handled by the

- EUSCI_A_UART_transmitData()
- EUSCI_A_UART_receiveData()
- EUSCI_A_UART_transmitAddress()
- EUSCI_A_UART_transmitBreak()

Managing the EUSI_UART interrupts and status are handled by the

- EUSCI_A_UART_enableInterrupt()
- EUSCI_A_UART_disableInterrupt()
- EUSCI_A_UART_getInterruptStatus()
- EUSCI_A_UART_clearInterruptFlag()
- EUSCI_A_UART_queryStatusFlags()

DMA related

- EUSCI_A_UART_getReceiveBufferAddressForDMA()
- EUSCI_A_UART_getTransmitBufferAddressForDMA()

13.3 Programming Example

The following example shows how to use the EUSI_UART API to initialize the EUSI_UART, transmit characters, and receive characters.

```
// Configure UART
if ( STATUS_FAIL == EUSCI_A_UART_init(EUSCI_A0_BASE,
            EUSCI_A_UART_CLOCKSOURCE_ACLK,
            CLOCK_VALUE,
            32768,
            EUSCI_A_UART_NO_PARITY,
            EUSCI_A_UART_LSB_FIRST,
            EUSCI_A_UART_ONE_STOP_BIT,
            EUSCI_A_UART_MODE,
            EUSCI_A_UART_LOW_FREQUENCY_BAUDRATE_GENERATION )){
       return;
   }

EUSCI_A_UART_enable(EUSCI_A0_BASE);

// Enable USCI_A0 RX interrupt
EUSCI_A_UART_enableInterrupt(EUSCI_A0_BASE,
                EUSCI_A_UART_RECEIVE_INTERRUPT);
```

14 EUSCI Synchronous Peripheral Interface (EUSCI_A_SPI)

Introduction 43
API Functions 43
Programming Example 44

14.1 Introduction

The Serial Peripheral Interface Bus or SPI bus is a synchronous serial data link standard named by Motorola that operates in full duplex mode. Devices communicate in master/slave mode where the master device initiates the data frame.

This library provides the API for handling a SPI communication using EUSCI.

The SPI module can be configured as either a master or a slave device.

The SPI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the module's input clock.

This driver is contained in `eusci_a_spi.c`, with `eusci_a_spi.h` containing the API definitions for use by applications.

14.2 Functions

To use the module as a master, the user must call EUSCI_A_SPI_masterInit() to configure the SPI Master. This is followed by enabling the SPI module using EUSCI_A_SPI_enable(). The interrupts are then enabled (if needed). **It** is recommended to enable the SPI module before enabling the interrupts. A data transmit is then initiated using EUSCI_A_SPI_transmitData() and then when the receive flag is set, the received data is read using EUSCI_A_SPI_receiveData() and this indicates that an RX/TX operation is complete.

To use the module as a slave, initialization is done using EUSCI_A_SPI_slaveInit() and this is followed by enabling the module using EUSCI_A_SPI_enable(). Following this, the interrupts may be enabled as needed. When the receive flag is set, data is first transmitted using EUSCI_A_SPI_transmitData() and this is followed by a data reception by EUSCI_A_SPI_receiveData()

The SPI API is broken into 3 groups of functions: those that deal with status and initialization, those that handle data, and those that manage interrupts.

The status and initialization of the SPI module are managed by

- EUSCI_A_SPI_masterInit
- EUSCI_A_SPI_slaveInit
- EUSCI_A_SPI_disable
- EUSCI_A_SPI_enable
- EUSCI_A_SPI_masterChangeClock
- EUSCI_A_SPI_isBusy

- EUSCI_A_SPI_select4PinFunctionality
- EUSCI_A_SPI_changeClockPhasePolarity

Data handling is done by

- EUSCI_A_SPI_transmitData
- EUSCI_A_SPI_receiveData

Interrupts from the SPI module are managed using

- EUSCI_A_SPI_disableInterrupt
- EUSCI_A_SPI_enableInterrupt
- EUSCI_A_SPI_getInterruptStatus
- EUSCI_A_SPI_clearInterruptFlag

DMA related

- EUSCI_A_SPI_getReceiveBufferAddressForDMA
- EUSCI_A_SPI_getTransmitBufferAddressForDMA

14.3 Programming Example

The following example shows how to use the SPI API to configure the SPI module as a master device, and how to do a simple send of data.

```
//Initialize slave to MSB first, inactive high clock polarity and 3 wire SPI
returnValue = EUSCI_A_SPI_slaveInit(EUSCI_A0_BASE,
        EUSCI_A_SPI_MSB_FIRST,
        EUSCI_A_SPI_PHASE_DATA_CHANGED_ONFIRST_CAPTURED_ON_NEXT,
        EUSCI_A_SPI_CLOCKPOLARITY_INACTIVITY_HIGH
        );

if (STATUS_FAIL == returnValue){
        return;
    }

//Enable SPI Module
EUSCI_A_SPI_enable(EUSCI_A0_BASE);

//Enable Receive interrupt
EUSCI_A_SPI_enableInterrupt(EUSCI_A0_BASE,
                EUSCI_A_SPI_RECEIVE_INTERRUPT
        );
```

15 EUSCI Synchronous Peripheral Interface (EUSCI_B_SPI)

Introduction 45
API Functions 45
Programming Example 46

15.1 Introduction

The Serial Peripheral Interface Bus or SPI bus is a synchronous serial data link standard named by Motorola that operates in full duplex mode. Devices communicate in master/slave mode where the master device initiates the data frame.

This library provides the API for handling a SPI communication using EUSCI.

The SPI module can be configured as either a master or a slave device.

The SPI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the module's input clock.

This driver is contained in `eusci_b_spi.c`, with `eusci_b_spi.h` containing the API definitions for use by applications.

15.2 Functions

To use the module as a master, the user must call EUSCI_B_SPI_masterInit() to configure the SPI Master. This is followed by enabling the SPI module using EUSCI_B_SPI_enable(). The interrupts are then enabled (if needed). **It** is recommended to enable the SPI module before enabling the interrupts. A data transmit is then initiated using EUSCI_B_SPI_transmitData() and then when the receive flag is set, the received data is read using EUSCI_B_SPI_receiveData() and this indicates that an RX/TX operation is complete.

To use the module as a slave, initialization is done using EUSCI_B_SPI_slaveInit() and this is followed by enabling the module using EUSCI_B_SPI_enable(). Following this, the interrupts may be enabled as needed. When the receive flag is set, data is first transmitted using EUSCI_B_SPI_transmitData() and this is followed by a data reception by EUSCI_B_SPI_receiveData()

The SPI API is broken into 3 groups of functions: those that deal with status and initialization, those that handle data, and those that manage interrupts.

The status and initialization of the SPI module are managed by

- EUSCI_B_SPI_masterInit
- EUSCI_B_SPI_slaveInit
- EUSCI_B_SPI_disable
- EUSCI_B_SPI_enable
- EUSCI_B_SPI_masterChangeClock
- EUSCI_B_SPI_isBusy

- EUSCI_B_SPI_select4PinFunctionality
- EUSCI_B_SPI_changeClockPhasePolarity

Data handling is done by

- EUSCI_B_SPI_transmitData
- EUSCI_B_SPI_receiveData

Interrupts from the SPI module are managed using

- EUSCI_B_SPI_disableInterrupt
- EUSCI_B_SPI_enableInterrupt
- EUSCI_B_SPI_getInterruptStatus
- EUSCI_B_SPI_clearInterruptFlag

DMA related

- EUSCI_B_SPI_getReceiveBufferAddressForDMA
- EUSCI_B_SPI_getTransmitBufferAddressForDMA

15.3 Programming Example

The following example shows how to use the SPI API to configure the SPI module as a master device, and how to do a simple send of data.

```
//Initialize slave to MSB first, inactive high clock polarity and 3 wire SPI
returnValue = EUSCI_B_SPI_slaveInit(EUSCI_B0_BASE,
        EUSCI_B_SPI_MSB_FIRST,
        EUSCI_B_SPI_PHASE_DATA_CHANGED_ONFIRST_CAPTURED_ON_NEXT,
        EUSCI_B_SPI_CLOCKPOLARITY_INACTIVITY_HIGH
        );

if (STATUS_FAIL == returnValue){
        return;
    }

//Enable SPI Module
EUSCI_B_SPI_enable(EUSCI_A0_BASE);

//Enable Receive interrupt
EUSCI_B_SPI_enableInterrupt(EUSCI_A0_BASE,
                EUSCI_B_SPI_RECEIVE_INTERRUPT
        );
```

16 EUSCI Inter-Integrated Circuit (EUSCI_B_I2C)

Introduction 47
API Functions 49
Programming Example 50

16.1 Introduction

In I2C mode, the eUSCI_B module provides an interface between the device and I2C-compatible devices connected by the two-wire I2C serial bus. External components attached to the I2C bus serially transmit and/or receive serial data to/from the eUSCI_B module through the 2-wire I2C interface. The Inter-Integrated Circuit (I2C) API provides a set of functions for using the MSP430Ware I2C modules. Functions are provided to initialize the I2C modules, to send and receive data, obtain status, and to manage interrupts for the I2C modules.

The I2C module provide the ability to communicate to other IC devices over an I2C bus. The I2C bus is specified to support devices that can both transmit and receive (write and read) data. Also, devices on the I2C bus can be designated as either a master or a slave. The MSP430Ware I2C modules support both sending and receiving data as either a master or a slave, and also support the simultaneous operation as both a master and a slave.

I2C module can generate interrupts. The I2C module configured as a master will generate interrupts when a transmit or receive operation is completed (or aborted due to an error). The I2C module configured as a slave will generate interrupts when data has been sent or requested by a master.

16.1.1 Master Operations

To drive the master module, the APIs need to be invoked in the following order

- **EUSCI_B_I2C_masterInit**
- **EUSCI_B_I2C_setSlaveAddress**
- **EUSCI_B_I2C_setMode**
- **EUSCI_B_I2C_enable**
- **EUSCI_B_I2C_enableInterrupt** (if interrupts are being used) This may be followed by the APIs for transmit or receive as required

The user must first initialize the I2C module and configure it as a master with a call to EUSCI_B_I2C_masterInit(). That function will set the clock and data rates. This is followed by a call to set the slave address with which the master intends to communicate with using EUSCI_B_I2C_setSlaveAddress. Then the mode of operation (transmit or receieve) is chosen using EUSCI_B_I2C_setMode. The I2C module may now be enabled using EUSCI_B_I2C_enable. It is recommneded to enable the EUSCI_B_I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below.

Master Single Byte Trasnmission

- EUSCI_B_I2C_masterSendSingleByte

Master Mulitple Byte Transmission

- EUSCI_B_I2C_masterMultiByteSendStart
- EUSCI_B_I2C_masterMultiByteSendNext
- EUSCI_B_I2C_masterMultiByteSendStop

Master Single Byte Reception

- EUSCI_B_I2C_masterReceiveStart
- EUSCI_B_I2C_masterSingleReceive

Master Multiple Byte Reception

- EUSCI_B_I2C_masterMultiByteReceiveStart
- EUSCI_B_I2C_masterMultiByteReceiveNext
- EUSCI_B_I2C_masterMultiByteReceiveFinish
- EUSCI_B_I2C_masterMultiByteReceiveStop

For the interrupt-driven transaction, the user must register an interrupt handler for the I2C devices and enable the I2C interrupt.

16.1.2 Slave Operations

To drive the slave module, the APIs need to be invoked in the following order

- **EUSCI_B_I2C_slaveInit**
- **EUSCI_B_I2C_setMode**
- **EUSCI_B_I2C_enable**
- **EUSCI_B_I2C_enableInterrupt** (if interrupts are being used) This may be followed by the APIs for transmit or receive as required

The user must first call the EUSCI_B_I2C_slaveInit to initialize the slave module in I2C mode and set the slave address. This is followed by a call to set the mode of operation (transmit or receive).The I2C module may now be enabled using EUSCI_B_I2C_enable. It is recommneded to enable the I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below.

Slave Transmission API

- EUSCI_B_I2C_slaveDataPut

Slave Reception API

- EUSCI_B_I2C_slaveDataGet

For the interrupt-driven transaction, the user must register an interrupt handler for the I2C devices and enable the I2C interrupt.

This driver is contained in `eusci_b_i2c.c`, with `eusci_b_i2c.h` containing the API definitions for use by applications.

16.2 API Functions

The eUSCI I2C API is broken into three groups of functions: those that deal with interrupts, those that handle status and initialization, and those that deal with sending and receiving data.

The I2C master and slave interrupts are handled by

- EUSCI_B_I2C_enableInterrupt
- EUSCI_B_I2C_disableInterrupt
- EUSCI_B_I2C_clearInterruptFlag
- EUSCI_B_I2C_getInterruptStatus

Status and initialization functions for the I2C modules are

- EUSCI_B_I2C_masterInit
- EUSCI_B_I2C_enable
- EUSCI_B_I2C_disable
- EUSCI_B_I2C_isBusBusy
- EUSCI_B_I2C_isBusy
- EUSCI_B_I2C_slaveInit
- EUSCI_B_I2C_interruptStatus
- EUSCI_B_I2C_setSlaveAddress
- EUSCI_B_I2C_setMode
- EUSCI_B_I2C_masterIsStopSent
- EUSCI_B_I2C_masterIsStartSent
- EUSCI_B_I2C_selectMasterEnvironmentSelect

Sending and receiving data from the I2C slave module is handled by

- EUSCI_B_I2C_slaveDataPut
- EUSCI_B_I2C_slaveDataGet

Sending and receiving data from the I2C slave module is handled by

- EUSCI_B_I2C_masterSendSingleByte
- EUSCI_B_I2C_masterSendStart
- EUSCI_B_I2C_masterMultiByteSendStart
- EUSCI_B_I2C_masterMultiByteSendNext
- EUSCI_B_I2C_masterMultiByteSendFinish
- EUSCI_B_I2C_masterMultiByteSendStop

- EUSCI_B_I2C_masterMultiByteReceiveNext
- EUSCI_B_I2C_masterMultiByteReceiveFinish
- EUSCI_B_I2C_masterMultiByteReceiveStop
- EUSCI_B_I2C_masterReceiveStart
- EUSCI_B_I2C_masterSingleReceive
- EUSCI_B_I2C_getReceiveBufferAddressForDMA
- EUSCI_B_I2C_getTransmitBufferAddressForDMA

DMA related

- EUSCI_B_I2C_getReceiveBufferAddressForDMA
- EUSCI_B_I2C_getTransmitBufferAddressForDMA

16.3 Programming Example

The following example shows how to use the I2C API to send data as a master.

```
//Initialize Slave
 EUSCI_B_I2C_slaveInit(EUSCI_B_B0_BASE,
             0x48,
             EUSCI_B_I2C_OWN_ADDRESS_OFFSET0,
             EUSCI_B_I2C_OWN_ADDRESS_ENABLE);

 //Set in receive mode
 EUSCI_B_I2C_setMode(EUSCI_B0_BASE,
             EUSCI_B_I2C_TRANSMIT_MODE);

 EUSCI_B_I2C_enable(EUSCI_B0_BASE);

 EUSCI_B_I2C_enableInterrupt(EUSCI_B0_BASE,
             EUSCI_B_I2C_TRANSMIT_INTERRUPT0 +
             EUSCI_B_I2C_STOP_INTERRUPT);
```

17 Flash Memory Controller

Introduction 51
API Functions 51
Programming Example 52

17.1 Introduction

The flash memory is byte, word, and long-word addressable and programmable. The flash memory module has an integrated controller that controls programming and erase operations. The flash main memory is partitioned into 512-byte segments. Single bits, bytes, or words can be written to flash memory, but a segment is the smallest size of the flash memory that can be erased. The flash memory is partitioned into main and information memory sections. There is no difference in the operation of the main and information memory sections. Code and data can be located in either section. The difference between the sections is the segment size. There are four information memory segments, A through D. Each information memory segment contains 128 bytes and can be erased individually. The bootstrap loader (BSL) memory consists of four segments, A through D. Each BSL memory segment contains 512 bytes and can be erased individually. The main memory segment size is 512 byte. See the device-specific data sheet for the start and end addresses of each bank, when available, and for the complete memory map of a device. This library provides the API for flash segment erase, flash writes and flash operation status check.

This driver is contained in `flash.c`, with `flash.h` containing the API definitions for use by applications.

17.2 API Functions

FLASH_segmentErase helps erase a single segment of the flash memory. A pointer to the flash segment being erased is passed on to this function.

FLASH_eraseCheck helps check if a specific number of bytes in flash are currently erased. A pointer to the starting location of the erase check and the number of bytes to be checked is passed into this function.

Depending on the kind of writes being performed to the flash, this library provides APIs for flash writes.

FLASH_write8 facilitates writing into the flash memory in byte format. FLASH_write16 facilitates writing into the flash memory in word format. FLASH_write32 facilitates writing into the flash memory in long format, pass by reference. FLASH_memoryFill32 facilitates writing into the flash memory in long format, pass by value. FLASH_status checks if the flash is currently busy erasing or programming.

The Flash API is broken into 3 groups of functions: those that deal with flash erase, those that write into flash, and those that give status of flash.

The flash erase operations are managed by

- FLASH_segmentErase
- FLASH_eraseCheck

- FLASH_bankErase

Flash writes are managed by

- FLASH_write8
- FLASH_write16
- FLASH_write32
- FLASH_memoryFill32

The status is given by

- FLASH_status
- FLASH_eraseCheck

17.3 Programming Example

The following example shows some flash operations using the APIs

```
do{
    FLASH_segmentErase(FLASH_BASE,
                       (unsigned char *)INFOD_START
                       );
    status = FLASH_eraseCheck(FLASH_BASE,
                              (unsigned char *)INFOD_START,
                              128
                              );
    }while(status == STATUS_FAIL);

    //Flash write
    FLASH_write32(FLASH_BASE,
                  calibration_data,
                  (unsigned long *)(INFOD_START),1);
```

18 GPIO

Introduction 53
API Functions 54
Programming Example 54

18.1 Introduction

The Digital I/O (GPIO) API provides a set of functions for using the MSP430Ware GPIO modules. Functions are provided to setup and enable use of input/output pins, setting them up with or without interrupts and those that access the pin value. The digital I/O features include:

- Independently programmable individual I/Os
- Any combination of input or output
- Individually configurable P1 and P2 interrupts. Some devices may include additional port interrupts.
- Independent input and output data registers
- Individually configurable pullup or pulldown resistors

Devices within the family may have up to twelve digital I/O ports implemented (P1 to P11 and PJ). Most ports contain eight I/O lines; however, some ports may contain less (see the device-specific data sheet for ports available). Each I/O line is individually configurable for input or output direction, and each can be individually read or written. Each I/O line is individually configurable for pullup or pulldown resistors, as well as, configurable drive strength, full or reduced. PJ contains only four I/O lines.

Ports P1 and P2 always have interrupt capability. Each interrupt for the P1 and P2 I/O lines can be individually enabled and configured to provide an interrupt on a rising or falling edge of an input signal. All P1 I/O lines source a single interrupt vector P1IV, and all P2 I/O lines source a different, single interrupt vector P2IV. On some devices, additional ports with interrupt capability may be available (see the device-specific data sheet for details) and contain their own respective interrupt vectors. Individual ports can be accessed as byte-wide ports or can be combined into word-wide ports and accessed via word formats. Port pairs P1/P2, P3/P4, P5/P6, P7/P8, etc., are associated with the names PA, PB, PC, PD, etc., respectively. All port registers are handled in this manner with this naming convention except for the interrupt vector registers, P1IV and P2IV; that is, PAIV does not exist. When writing to port PA with word operations, all 16 bits are written to the port. When writing to the lower byte of the PA port using byte operations, the upper byte remains unchanged. Similarly, writing to the upper byte of the PA port using byte instructions leaves the lower byte unchanged. When writing to a port that contains less than the maximum number of bits possible, the unused bits are a "don't care". Ports PB, PC, PD, PE, and PF behave similarly.

Reading of the PA port using word operations causes all 16 bits to be transferred to the destination. Reading the lower or upper byte of the PA port (P1 or P2) and storing to memory using byte operations causes only the lower or upper byte to be transferred to the destination, respectively. Reading of the PA port and storing to a general-purpose register using byte operations causes the byte transferred to be written to the least significant byte of the register. The upper significant byte of the destination register is cleared automatically. Ports PB, PC, PD, PE, and PF behave similarly. When reading from ports that contain less than the maximum bits possible, unused bits are read as zeros (similarly for port PJ).

The GPIO pin may be configured as an I/O pin with GPIO_setAsOutputPin(), GPIO_setAsInputPin(), GPIO_setAsInputPinWithPullDownresistor() or GPIO_setAsInputPinWithPullUpresistor(). The GPIO pin may instead be configured to operate in the Peripheral Module assigned function by configuring the GPIO using GPIO_setAsPeripheralModuleFunctionOutputPin() or GPIO_setAsPeripheralModuleFunctionInputPin().

This driver is contained in `gpio.c`, with `gpio.h` containing the API definitions for use by applications.

18.2 API Functions

The GPIO API is broken into three groups of functions: those that deal with configuring the GPIO pins, those that deal with interrupts, and those that access the pin value.

The GPIO pins are configured with

- GPIO_setAsOutputPin()
- GPIO_setAsInputPin()
- GPIO_setAsInputPinWithPullDownresistor()
- GPIO_setAsInputPinWithPullUpresistor()
- GPIO_setDriveStrength()
- GPIO_setAsPeripheralModuleFunctionOutputPin()
- GPIO_setAsPeripheralModuleFunctionInputPin()

The GPIO interrupts are handled with

- GPIO_enableInterrupt()
- GPIO_disbleInterrupt()
- GPIO_clearInterruptFlag()
- GPIO_getInterruptStatus()
- GPIO_interruptEdgeSelect()

The GPIO pin state is accessed with

- GPIO_setOutputHighOnPin()
- GPIO_setOutputLowOnPin()
- GPIO_toggleOutputOnPin()
- GPIO_getInputPinValue()

18.3 Programming Example

The following example shows how to use the GPIO API.

```
  // Set P1.0 to output direction
GPIO_setAsOutputPin(GPIO_PORT_P1,
                    GPIO_PIN0
                    );

// Set P1.4 to input direction
GPIO_setAsInputPin(GPIO_PORT_P1,
                    GPIO_PIN4
                    );

while (1)
{
  // Test P1.4
  if(GPIO_INPUT_PIN_HIGH == GPIO_getInputPinValue(
                                    GPIO_PORT_P1,
                                    GPIO_PIN4
                                    ))
  {
    // if P1.4 set, set P1.0
    GPIO_setOutputHighOnPin(
                    GPIO_PORT_P1,
                    GPIO_PIN0
                    );
  }
  else
  {
    // else reset
    GPIO_setOutputLowOnPin(
                    GPIO_PORT_P1,
                    GPIO_PIN0
                    );
  }
}
```

19 LDO-PWR

Introduction 57
API Functions 57
Programming Example 58

19.1 Introduction

The features of the LDO-PWR module include:

- Integrated 3.3-V LDO regulator with sufficient output to power the entire MSP430Ź microcontroller and system circuitry from 5-V external supply
- Current-limiting capability on 3.3-V LDO output with detection flag and interrupt generation
- LDO input voltage detection flag and interrupt generation

The LDO-PWR power system incorporates an integrated 3.3-V LDO regulator that allows the entire MSP430 microcontroller to be powered from nominal 5-V LDOI when it is made available from the system. Alternatively, the power system can supply power only to other components within the system, or it can be unused altogether.

This driver is contained in `ldopwr.c`, with `ldopwr.h` containing the API definitions for use by applications.

19.2 API Functions

The LDOPWR configuration is handled by

- LDOPWR_unLockConfiguration()
- LDOPWR_lockConfiguration()
- LDOPWR_enablePort_U_inputs()
- LDOPWR_disablePort_U_inputs()
- LDOPWR_enablePort_U_outputs()
- LDOPWR_disablePort_U_outputs()
- LDOPWR_enable()
- LDOPWR_disable()
- LDOPWR_enableOverloadAutoOff()
- LDOPWR_disableOverloadAutoOff()

Handling the read/write of output data is handled by

- LDOPWR_getPort_U1_inputData()
- LDOPWR_getPort_U0_inputData()
- LDOPWR_getPort_U1_outputData()
- LDOPWR_getPort_U0_outputData()

- LDOPWR_getOverloadAutoOffStatus()
- LDOPWR_setPort_U0_outputData()
- LDOPWR_togglePort_U1_outputData()
- LDOPWR_togglePort_U0_outputData()
- LDOPWR_setPort_U1_outputData()

The interrupt and status operations are handled by

- LDOPWR_enableInterrupt()
- LDOPWR_disableInterrupt()
- LDOPWR_getInterruptStatus()
- LDOPWR_clearInterruptStatus()
- LDOPWR_isLDOInputValid()
- LDOPWR_getOverloadAutoOffStatus()

19.3 Programming Example

The following example shows how to use the LDO-PWR API.

```
{
  // Enable access to config registers
  LDOPWR_unLockConfiguration(LDOPWR_BASE);

  // Configure PU.0 as output pins
  LDOPWR_enablePort_U_outputs(LDOPWR_BASE);

  //Set PU.1 = high
  LDOPWR_setPort_U1_outputData(LDOPWR_BASE,
                               LDOPWR_PORTU_PIN_HIGH
                                                                  );

  //Set PU.0 = low
  LDOPWR_setPort_U0_outputData(LDOPWR_BASE,
                               LDOPWR_PORTU_PIN_LOW
                               );

  // Enable LDO overload indication interrupt
  LDOPWR_enableInterrupt(LDOPWR_BASE,
                         LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                         );

  // Disbale access to config registers
  LDOPWR_lockConfiguration(LDOPWR_BASE);

  // continuous loop
  while(1)
  {
    // Delay
    for(i=50000;i>0;i--);

    // Enable access to config registers
    LDOPWR_unLockConfiguration(LDOPWR_BASE);

    // XOR PU.0/1
    LDOPWR_togglePort_U1_outputData(LDOPWR_BASE);
```

```
    LDOPWR_togglePort_U0_outputData(LDOPWR_BASE);

    // Disbale access to config registers
    LDOPWR_lockConfiguration(LDOPWR_BASE);
  }
}


//*****************************************************************************
//
// This is the LDO_PWR_VECTOR interrupt vector service routine.
//
//*****************************************************************************
__interrupt void LDOInterruptHandler(void)
{
  if(LDOPWR_getInterruptStatus(LDOPWR_BASE,
                               LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                               ))

  {
    // Enable access to config registers
    LDOPWR_unLockConfiguration(LDOPWR_BASE);

   // Software clear IFG
    LDOPWR_clearInterruptStatus(LDOPWR_BASE,
                                LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                                );

   // Disable access to config registers
   LDOPWR_lockConfiguration(LDOPWR_BASE);

   // Over load indication; take necessary steps in application firmware
   while(1);

  }
}
```

20 32-Bit Hardware Multiplier (MPY32)

Introduction 61
API Functions 61
Programming Example 62

20.1 Introduction

The 32-Bit Hardware Multiplier (MPY32) API provides a set of functions for using the MSP430Ware MPY32 modules. Functions are provided to setup the MPY32 modules, set the operand registers, and obtain the results.

The MPY32 Modules does not generate any interrupts.

This driver is contained in `mpy32.c`, with `mpy32.h` containing the API definitions for use by applications.

20.2 API Functions

The MPY32 API is broken into three groups of functions: those that control the settings, those that set the operand registers, and those that return the results, sum extension, and carry bit value.

The settings are handled by

- MPY32_setWriteDelay
- MPY32_setSaturationMode
- MPY32_resetSaturationMode
- MPY32_setFractionMode
- MPY32_resetFractionMode

The operand registers are set by

- MPY32_setOperandOne8Bit
- MPY32_setOperandOne16Bit
- MPY32_setOperandOne24Bit
- MPY32_setOperandOne32Bit
- MPY32_setOperandTwo8Bit
- MPY32_setOperandTwo16Bit
- MPY32_setOperandTwo24Bit
- MPY32_setOperandTwo32Bit

The results can be returned by

- MPY32_getResult8Bit
- MPY32_getResult16Bit
- MPY32_getResult24Bit

- MPY32_getResult32Bit
- MPY32_getResult64Bit
- MPY32_getSumExtension
- MPY32_getCarryBitValue

20.3 Programming Example

The following example shows how to initialize and use the MPY32 API to calculate a 16-bit by 16-bit unsigned multiplication operation.

```
WDT_hold(WDT_A_BASE);   // Stop WDT

// Set a 16-bit Operand into the specific Operand 1 register to specify
 // unsigned multiplication
MPY32_setOperandOne16Bit(MPY32_BASE,
                         MPY32_MULTIPLY_UNSIGNED,
                         0x1234);
// Set Operand 2 to begin the multiplication operation
MPY32_setOperandTwo16Bit(MPY32_BASE,
                         0x5678);

__bis_SR_register(LPM4_bits);             // Enter LPM4
__no_operation();                         // BREAKPOINT HERE to verify the
                                           // correct result in the registers
```

21 Port Mapping Controller

Introduction 63
API Functions 63
Programming Example 63

21.1 Introduction

The port mapping controller allows the flexible and reconfigurable mapping of digital functions to port pins. The port mapping controller features are:

- Configuration protected by write access key.
- Default mapping provided for each port pin (device-dependent, the device pinout in the device-specific data sheet).
- Mapping can be reconfigured during runtime.
- Each output signal can be mapped to several output pins.

This driver is contained in `pmap.c`, with `pmap.h` containing the API definitions for use by applications.

21.2 API Functions

The MSP430ware API that configures Port Mapping is PMAP_configurePorts()

It needs the following data to configure port mapping. portMapping - pointer to init Data PxMAPy - pointer start of first Port Mapper to initialize numberOfPorts - number of Ports to initialize portMapReconfigure - to enable/disable reconfiguration

21.3 Programming Example

The following example shows some Port Mapping Controller operations using the APIs

```
    const unsigned char port_mapping[] = {
            //Port P4:
            PM_TB0CCR0A,
            PM_TB0CCR1A,
            PM_TB0CCR2A,
            PM_TB0CCR3A,
            PM_TB0CCR4A,
            PM_TB0CCR5A,
            PM_TB0CCR6A,
            PM_NONE
    };

    //CONFIGURE PORTS- pass the port_mapping array, start @ P4MAP01, initialize
//a single port, do not allow run-time reconfiguration of port mapping

    PMAP_configurePorts(P4MAP_BASE,
```

```
(const unsigned char  *)port_mapping,
(unsigned char  *)&P4MAP01,
1,
PMAP_DISABLE_RECONFIGURATION
);
```

22 Power Management Module (PMM)

Introduction 65
API Functions 66
Programming Example 68

22.1 Introduction

The PMM manages the following internal circuitry:

- An integrated low-dropout voltage regulator (LDO) that produces a secondary core voltage (VCORE) from the primary voltage that is applied to the device (DVCC)
- Supply voltage supervisors (SVS) and supply voltage monitors (SVM) for the primary voltage (DVCC) and the secondary voltage (VCORE). The SVS and SVM include programmable threshold levels and power-fail indicators. Therefore, the PMM plays a crucial role in defining the maximum performance, valid voltage conditions, and current consumption for an application running on an MSP430x5xx or MSP430x6xx device. The secondary voltage that is generated by the integrated LDO, VCORE, is programmable to one of four core voltage levels, shown as 0, 1, 2, and 3. Each increase in VCORE allows the CPU to operate at a higher maximum frequency. The values of these frequencies are specified in the device-specific data sheet. This feature allows the user the flexibility to trade power consumption in active and low-power modes for different degrees of maximum performance and minimum supply voltage.

NOTE: To align with the nomenclature in the MSP430x5xx/MSP430x6xx Family UserŠs Guide, the primary voltage domain (DVCC) is referred to as the high-side voltage (SvsH/SVMH) and the secondary voltage domain (VCORE) is referred to as the low-side voltage (SvsL/SvmL).

Moving between the different VCORE voltages requires a specific sequence of events and can be done only one level at a time; for example, to change from level 0 to level 3, the application code must step through level 1 and level 2.

VCORE increase: 1. SvmL monitor level is incremented. 2. VCORE level is incremented. 3. The SvmL Level Reached Interrupt Flag (SVSMLVLRIFG) in the PMMIFG register is polled. When asserted, SVSMLVLRIFG indicates that the VCORE voltage has reached its next level. 4. SvsL is increased. SvsL is changed last, because if SVSL were incremented prior to VCORE, it would potentially cause a reset.

VCORE decrease: 5. Decrement SvmL and SVSL levels. 6. Decrement VCORE. The PMM_setVCore() function appropriately handles an increase or decrease of the core voltage. NOTE: The procedure recommended above provides a workaround for the erratum FLASH37. See the device-specific erratasheet to determine if a device is affected by FLASH37. The workaround is also highlighted in the source code for the PMM library

Recommended SVS and SVM Settings The SVS and SVM on both the high side and the low side are enabled in normal performance mode following a brown-out reset condition. The device is held in reset until the SVS and SVM verify that the external and core voltages meet the minimum requirements of the default core voltage, which is level zero. The SVS and SVM remain enabled unless disabled by the firmware. The low-side SVS and SVM are useful for verifying the startup conditions and for verifying any modification to the core voltage. However, in their default mode, they prevent the CPU from executing code on wake-up from low-power modes 2, 3, and 4 for a full 150 μs, not 5 μs. This is because, in their default states, the SVSL and SvmL are powered down in the low-power mode of the PMM and need time for their comparators to wake and stabilize

before they can verify the voltage condition and release the CPU for execution. Note that the high-side SVS and SVM do not influence the wake time from low-power modes. If the wake-up from low-power modes needs to be shortened to 5 μs, the SVSL and SvmL should be disabled after the initialization of the core voltage at the beginning of the application. Disabling SVSL and SvmL prevents them from gating the CPU on wake-up from LPM2, LPM3, and LPM4. The application is still protected on the high side with SvsH and SVMH. The PMM_setVCore() function automatically enables and disables the SVS and SVM as necessary if a non-zero core voltage level is required. If the application does not require a change in the core voltage (that is, when the target MCLK is less than 8 MHz), the PMM_disableSVSLSvmL() and PMM_enableSvsHReset() macros can be used to disable the low-side SVS and SVM circuitry and enable only the high-side SVS POR reset, respectively.

Setting SVS/SVM Threshold Levels The voltage thresholds for the SVS and SVM modules are programmable. On the high side, there are two bit fields that control these threshold levels Ű the SvsHRVL and SVSMHRRL. The SvsHRVL field defines the voltage threshold at which the SvsH triggers a reset (also known as the SvsH ON voltage level). The SVSMHRRL field defines the voltage threshold at which the SvsH releases the device from a reset (also known as SvsH OFF voltage level). The MSP430x5xx/MSP430x6xx Family UserŠs Guide (SLAU208) [1] recommends the settings shown in Table 1 when setting these bits. The PMM_setVCore() function follows these recommendations and ensures that the SVS levels match the core voltage levels that are used.

Advanced SVS Controls and Trade-offs In addition to the default SVS settings that are provided with the PMM_setVCore() function, the SVS/SVM modules can be optimized for wake-up speed, response time (propagation delay), and current consumption, as needed. The following controls can be optimized for the SVS/SVM modules:

- Protection in low power modes - LPM2, LPM3, and LPM4
- Wake-up time from LPM2, LPM3, and LPM4
- Response time to react to an SVS event Selecting the LPM option, wake-up time, and response time that is best suited for the application is left to the user. A few typical examples illustrate the trade-offs: Case A: The most robust protection that stays on in LPMs and has the fastest response and wake-up time consumes the most power. Case B: With SVS high side active only in AM, no protection in LPMs, slow wake-up, and slow response time has SVS protection with the least current consumption. Case C: An optimized case is described - turn off the low-side monitor and supervisor, thereby saving power while keeping response time fast on the high side to help with timing critical applications. The user can call the PMM_setVCore() function, which configures SVS/SVM high side and low side with the recommended or default configurations, or can call the APIs provided to control the parameters as the application demands.

Any writes to the SVSMLCTL and SVSMHCTL registers require a delay time for these registers to settle before the new settings take effect. This delay time is dependent on whether the SVS and SVM modules are configured for normal or full performance. See device-specific data sheet for exact delay times.

22.2 API Functions

PMM_enableSvsL() / **PMM_disableSvsL()** Enables or disables the low-side SVS circuitry

PMM_enableSvmL() / **PMM_disableSvmL()** Enables or disables the low-side SVM circuitry

PMM_enableSvsH() / **PMM_disableSvsH()** Enables or disables the high-side SVS circuitry

PMM_enableSVMH() / **PMM_disableSVMH()** Enables or disables the high-side SVM circuitry

PMM_enableSvsLSvmL() / **PMM_disableSvsLSvmL()** Enables or disables the low-side SVS and SVM circuitry

PMM_enableSvsHSvmH() / **PMM_disableSvsHSvmH()** Enables or disables the high-side SVS and SVM circuitry

PMM_enableSvsLReset() / **PMM_disableSvsLReset()** Enables or disables the POR signal generation when a low-voltage event is registered by the low-side SVS

PMM_enableSvmLInterrupt() / **PMM_disableSvmLInterrupt()** Enables or disables the interrupt generation when a low-voltage event is registered by the low-side SVM

PMM_enableSvsHReset() / **PMM_disableSvsHReset()** Enables or disables the POR signal generation when a low-voltage event is registered by the high-side SVS

PMM_enableSVMHInterrupt() / **PMM_disableSVMHInterrupt()** Enables or disables the interrupt generation when a low-voltage event is registered by the high-side SVM

PMM_clearPMMIFGS() Clear all interrupt flags for the PMM

PMM_SvsLEnabledInLPMFastWake() Enables supervisor low side in LPM with twake-up-fast from LPM2, LPM3, and LPM4

PMM_SvsLEnabledInLPMSlowWake() Enables supervisor low side in LPM with twake-up-slow from LPM2, LPM3, and LPM4

PMM_SvsLDisabledInLPMFastWake() Disables supervisor low side in LPM with twake-up-fast from LPM2, LPM3, and LPM4

PMM_SvsLDisabledInLPMSlowWake() Disables supervisor low side in LPM with twake-up-slow from LPM2, LPM3, and LPM4

PMM_SvsHEnabledInLPMNormPerf() Enables supervisor high side in LPM with tpd = 20 μs(1)

PMM_SvsHEnabledInLPMFullPerf() Enables supervisor high side in LPM with tpd = 2.5 μs(1)

PMM_SvsHDisabledInLPMNormPerf() Disables supervisor high side in LPM with tpd = 20 μs(1)

PMM_SvsHDisabledInLPMFullPerf() Disables supervisor high side in LPM with tpd = 2.5 μs(1)

PMM_SvsLOptimizedInLPMFastWake() Optimized to provide twake-up-fast from LPM2, LPM3, and LPM4 with least power

PMM_SvsHOptimizedinLPMFullPerf() Optimized to provide tpd = 2.5 μs(1) in LPM with least power

PMM_getInterruptStatus() Returns interrupt status of the PMM module

PMM_setVCore() Sets the appropriate VCORE level. Calls the PMM_setVCoreUp() or PMM_setVCoreDown() function the required number of times depending on the current VCORE level, because the levels must be stepped through individually. A status indicator equal to STATUS_SUCCESS or STATUS_FAIL that indicates a valid or invalid VCORE transition, respectively. An invalid VCORE transition exists if DVCC is less than the minimum required voltage for the target VCORE voltage.

This driver is contained in `pmm.c`, with `pmm.h` containing the API definitions for use by applications.

22.3 Programming Example

The following example shows some pmm operations using the APIs

```
//Use the line below to bring the level back to 0
    status = PMM_setVCore(PMM_BASE,
        PMMCOREV_0
        );

    //Set P1.0 to output direction
    GPIO_setAsOutputPin(
        GPIO_PORT_P1,
        GPIO_PIN0
        );

    //continuous loop
    while (1)
    {
        //Toggle P1.0
        GPIO_toggleOutputOnPin(
            GPIO_PORT_P1,
            GPIO_PIN0
            );
        //Delay
        __delay_cycles(20000);
    }
```

23 RAM Controller

Introduction 69
API Functions 69
Programming Example 69

23.1 Introduction

The RAMCTL provides access to the different power modes of the RAM. The RAMCTL allows the ability to reduce the leakage current while the CPU is off. The RAM can also be switched off. In retention mode, the RAM content is saved while the RAM content is lost in off mode. The RAM is partitioned in sectors, typically of 4KB (sector) size. See the device-specific data sheet for actual block allocation and size. Each sector is controlled by the RAM controller RAM Sector Off control bit (RCRSyOFF) of the RAMCTL Control 0 register (RCCTL0). The RCCTL0 register is protected with a key. Only if the correct key is written during a word write, the RCCTL0 register content can be modified. Byte write accesses or write accesses with a wrong key are ignored.

This driver is contained in `ramcontroller.c`, with `ramcontroller.h` containing the API definitions for use by applications.

23.2 API Functions

The MSP430ware API that configure the RAM controller are:

RAM_setSectorOff() - Set specified RAM sector off RAM_getSectorState() - Get RAM sector ON/OFF status

23.3 Programming Example

The following example shows some RAM Controller operations using the APIs

```
//Start timer
Timer_startUpMode(   TIMER_B0_BASE,
    TIMER_CLOCKSOURCE_ACLK,
    TIMER_CLOCKSOURCE_DIVIDER_1,
    25000,
    TIMER_TAIE_INTERRUPT_DISABLE,
    TIMER_CAPTURECOMPARE_INTERRUPT_ENABLE,
    TIMER_DO_CLEAR
    );

//RAM controller sector off
RAM_setSectorOff(RAM_BASE,
    RAMCONTROL_SECTOR2
    ) ;


//Enter LPM0, enable interrupts
__bis_SR_register(LPM3_bits + GIE);
```

```
    //For debugger
    __no_operation();
}

//****************************************************************************
//
//This is the Timer B0 interrupt vector service routine.
//
//****************************************************************************
#pragma vector=TIMERB0_VECTOR
__interrupt void TIMERB0_ISR (void)
{
    returnValue = RAM_getSectorState(RAM_BASE,
        RAM_SECTOR0 +
        RAM_SECTOR1 +
        RAM_SECTOR2 +
        RAM_SECTOR3);

}
```

24 Internal Reference (REF)

Introduction 71
API Functions 71
Programming Example 72

24.1 Introduction

The Internal Reference (REF) API provides a set of functions for using the MSP430Ware REF modules. Functions are provided to setup and enable use of the Reference voltage, enable or disable the internal temperature sensor, and view the status of the inner workings of the REF module.

The reference module (REF) is responsible for generation of all critical reference voltages that can be used by various analog peripherals in a given device. These include, but are not necessarily limited to, the ADC10_A, ADC12_A, DAC12_A, LCD_B, and COMP_B modules dependent upon the particular device. The heart of the reference system is the bandgap from which all other references are derived by unity or non-inverting gain stages. The REFGEN sub-system consists of the bandgap, the bandgap bias, and the non-inverting buffer stage which generates the three primary voltage reference available in the system, namely 1.5 V, 2.0 V, and 2.5 V. In addition, when enabled, a buffered bandgap voltage is also available.

This driver is contained in `ref.c`, with `ref.h` containing the API definitions for use by applications.

24.2 API Functions

The DMA API is broken into three groups of functions: those that deal with the reference voltage, those that handle the internal temperature sensor, and those that return the status of the REF module.

The reference voltage of the REF module is handled by

- REF_setReferenceVoltage
- REF_enableReferenceVoltageOutput
- REF_disableReferenceVoltageOutput
- REF_enableReferenceVoltage
- REF_disableReferenceVoltage

The internal temperature sensor is handled by

- REF_disableTempSensor
- REF_enableTempSensor

The status of the REF module is handled by

- REF_getBandgapMode
- REF_isBandgapActive

- REF_isRefGenBusy
- REF_isRefGen

24.3 Programming Example

The following example shows how to initialize and use the REF API with the ADC12_A module to use as a positive reference to the analog signal input.

```
// By default, REFMSTR=1 => REFCTL is used to configure the internal reference

// If ref generator busy, WAIT
while(REF_refGenBusyStatus(REF_BASE));
// Select internal ref = 2.5V
REF_setReferenceVoltage(REF_BASE,
                        REF_VREF2_5V);
// Internal Reference ON
REF_enableReferenceVoltage(REF_BASE);

__delay_cycles(75);                       // Delay (~75us) for Ref to settle

// Initialize the ADC12_A Module
/*
Base address of ADC12_A Module
Use internal ADC12_A bit as sample/hold signal to start conversion
USE MODOSC 5MHZ Digital Oscillator as clock source
Use default clock divider of 1
  */
ADC12_A_init(ADC12_A_BASE,
           ADC12_A_SAMPLEHOLDSOURCE_SC,
           ADC12_A_CLOCKSOURCE_ADC12OSC,
           ADC12_A_CLOCKDIVIDEBY_1);
/*
Base address of ADC12 Module
For memory buffers 0-7 sample/hold for 64 clock cycles
For memory buffers 8-15 sample/hold for 4 clock cycles (default)
Disable Multiple Sampling
  */
ADC12_A_setupSamplingTimer(ADC12_A_BASE,
                         ADC12_A_CYCLEHOLD_64_CYCLES,
                         ADC12_A_CYCLEHOLD_4_CYCLES,
                         ADC12_A_MULTIPLESAMPLESENABLE);

// Configure Memory Buffer
/*
Base address of the ADC12 Module
Configure memory buffer 0
Map input A0 to memory buffer 0
Vref+ = Vref+ (INT)
Vref- = AVss
  */
ADC12_A_memoryConfigure(ADC12_A_BASE,
                      ADC12_A_MEMORY_0,
                      ADC12_A_INPUT_A0,
                      ADC12_A_VREFPOS_INT,
                      ADC12_A_VREFNEG_AVSS,
                      ADC12_A_NOTENDOFSEQUENCE);

while (1)
{
  // Enable/Start sampling and conversion
  /*
```

```
Base address of ADC12 Module
Start the conversion into memory buffer 0
Use the single-channel, single-conversion mode
    */
   ADC12_A_startConversion(ADC12_A_BASE,
                           ADC12_A_MEMORY_0,
                           ADC12_A_SINGLECHANNEL);

   // Poll for interrupt on memory buffer 0
   while(!ADC12_A_interruptStatus(ADC12_A_BASE, ADC12IFG0));

   __no_operation();                       // SET BREAKPOINT HERE
 }
```

25 Real-Time Clock (RTC)

Introduction 75
API Functions 75
Programming Example 76

25.1 Introduction

The Real Time Clock (RTC) API provides a set of functions for using the MSP430Ware RTC modules. Functions are provided to calibrate the clock, initialize the RTC modules in Calendar mode, and setup conditions for, and enable, interrupts for the RTC modules. If an RTC_A_A module is used, then Counter mode may also be intialized, as well as prescale counters.

The RTC module provides the ability to keep track of the current time and date in calendar mode, or can be setup as a 32-bit counter (RTC_A_A Only).

The RTC module generates multiple interrupts. There are 2 interrupts that can be defined in calendar mode, and 1 interrupt in counter mode for counter overflow, as well as an interrupt for each prescaler.

This driver is contained in `rtc_a.c`, with `rtc_a.h` containing the API definitions for use by applications.

25.2 API Functions

The RTC API is broken into 4 groups of functions: clock settings, calender mode, counter mode, and interrupt condition setup and enable functions.

The RTC clock settings are handled by

- RTC_A_startClock
- RTC_A_holdClock
- RTC_A_setCalibrationFrequency
- RTC_A_setCalibrationData

The RTC Calender Mode is initialized and setup by

- RTC_A_calenderInit
- RTC_A_getCalenderTime
- RTC_A_getPrescaleValue
- RTC_A_setPrescaleValue

The RTC Counter Mode is initialized and setup by

- RTC_A_counterInit
- RTC_A_getCounterValue
- RTC_A_setCounterValue

- RTC_A_counterPrescaleInit
- RTC_A_counterPrescaleHold
- RTC_A_counterPrescaleStart
- RTC_A_getPrescaleValue
- RTC_A_setPrescaleValue

The RTC interrupts are handled by

- RTC_A_setCalenderAlarm
- RTC_A_setCalenderEvent
- RTC_A_definePrescaleEvent
- RTC_A_enableInterrupt
- RTC_A_disableInterrupt
- RTC_A_getInterruptStatus
- RTC_A_clearInterrupt

25.3 Programming Example

The following example shows how to initialize and use the RTC API to setup Calender Mode with the current time and various interrupts.

```
  //Initialize Calendar Mode of RTC
    /*
 Base Address of the RTC_A
 Pass in current time, intialized above
 Use BCD as Calendar Register Format
     */
    RTC_A_calendarInit(RTC_A_BASE,
        currentTime,
        RTC_A_FORMAT_BCD);

    //Setup Calendar Alarm for 5:00pm on the 5th day of the week.
    //Note: Does not specify day of the week.
    RTC_A_setCalendarAlarm(RTC_A_BASE,
        0x00,
        0x17,
        RTC_A_ALARMCONDITION_OFF,
        0x05);

    //Specify an interrupt to assert every minute
    RTC_A_setCalendarEvent(RTC_A_BASE,
        RTC_A_CALENDAREVENT_MINUTECHANGE);

    //Enable interrupt for RTC Ready Status, which asserts when the RTC
    //Calendar registers are ready to read.
    //Also, enable interrupts for the Calendar alarm and Calendar event.
    RTC_A_enableInterrupt(RTC_A_BASE,
        RTCRDYIE + RTCTEVIE + RTCAIE);

    //Start RTC Clock
    RTC_A_startClock(RTC_A_BASE);

    //Enter LPM3 mode with interrupts enabled
    __bis_SR_register(LPM3_bits + GIE);
    __no_operation();
```

26 Real-Time Clock (RTC)

Introduction 77
API Functions 77
Programming Example 78

26.1 Introduction

The Real Time Clock (RTC) API provides a set of functions for using the MSP430Ware RTC modules. Functions are provided to calibrate the clock, initialize the RTC modules in Calendar mode, and setup conditions for, and enable, interrupts for the RTC modules. If an RTC_B_A module is used, then Counter mode may also be intialized, as well as prescale counters.

The RTC module provides the ability to keep track of the current time and date in calendar mode, or can be setup as a 32-bit counter (RTC_B_A Only).

The RTC module generates multiple interrupts. There are 2 interrupts that can be defined in calendar mode, and 1 interrupt in counter mode for counter overflow, as well as an interrupt for each prescaler.

This driver is contained in `rtc_b.c`, with `rtc_b.h` containing the API definitions for use by applications.

26.2 API Functions

The RTC API is broken into 4 groups of functions: clock settings, calender mode, counter mode, and interrupt condition setup and enable functions.

The RTC clock settings are handled by

- RTC_B_startClock
- RTC_B_holdClock
- RTC_B_setCalibrationFrequency
- RTC_B_setCalibrationData

The RTC Calender Mode is initialized and setup by

- RTC_B_calenderInit
- RTC_B_getCalenderTime
- RTC_B_getPrescaleValue
- RTC_B_setPrescaleValue

The RTC interrupts are handled by

- RTC_B_setCalenderAlarm
- RTC_B_setCalenderEvent
- RTC_B_definePrescaleEvent

- RTC_B_enableInterrupt
- RTC_B_disableInterrupt
- RTC_B_getInterruptStatus
- RTC_B_clearInterrupt

The RTC conversions are handled by

- RTC_B_convertBCDToBinary
- RTC_B_convertBinaryToBCD

26.3 Programming Example

The following example shows how to initialize and use the RTC API to setup Calender Mode with the current time and various interrupts.

```
  //Initialize Calendar Mode of RTC
    /*
 Base Address of the RTC_B_A
 Pass in current time, intialized above
 Use BCD as Calendar Register Format
     */
    RTC_B_calendarInit(RTC_B_BASE,
        currentTime,
        RTC_B_FORMAT_BCD);

    //Setup Calendar Alarm for 5:00pm on the 5th day of the week.
    //Note: Does not specify day of the week.
    RTC_B_setCalendarAlarm(RTC_B_BASE,
        0x00,
        0x17,
        RTC_B_ALARMCONDITION_OFF,
        0x05);

    //Specify an interrupt to assert every minute
    RTC_B_setCalendarEvent(RTC_B_BASE,
        RTC_B_CALENDAREVENT_MINUTECHANGE);

    //Enable interrupt for RTC Ready Status, which asserts when the RTC
    //Calendar registers are ready to read.
    //Also, enable interrupts for the Calendar alarm and Calendar event.
    RTC_B_enableInterrupt(RTC_B_BASE,
        RTCRDYIE + RTCTEVIE + RTCAIE);

    //Start RTC Clock
    RTC_B_startClock(RTC_B_BASE);

    //Enter LPM3 mode with interrupts enabled
    __bis_SR_register(LPM3_bits + GIE);
    __no_operation();
```

27 Real-Time Clock (RTC_C)

Introduction 79
API Functions 79
Programming Example 80

27.1 Introduction

The Real Time Clock (RTC_C) API provides a set of functions for using the MSP430Ware RTC_C modules. Functions are provided to calibrate the clock, initialize the RTC_C modules in Calendar mode, and setup conditions for, and enable, interrupts for the RTC_C modules.

The RTC_C module provides the ability to keep track of the current time and date in calendar mode.

The RTC_C module generates multiple interrupts. There are 2 interrupts that can be defined in calendar mode, and 1 interrupt in counter mode for counter overflow, as well as an interrupt for each prescaler.

This driver is contained in `rtc_c.c`, with `rtc_c.h` containing the API definitions for use by applications.

27.2 API Functions

The RTC_C API is broken into 4 groups of functions: clock settings, calender mode, counter mode, and interrupt condition setup and enable functions.

The RTC_C clock settings are handled by

- RTC_C_startClock
- RTC_C_holdClock
- RTC_C_setCalibrationFrequency
- RTC_C_setCalibrationData
- RTC_C_setTemperatureCompensation

The RTC_C Calender Mode is initialized and setup by

- RTC_C_calenderInit
- RTC_C_getCalenderTime
- RTC_C_getPrescaleValue
- RTC_C_setPrescaleValue

The RTC_C interrupts are handled by

- RTC_C_setCalenderAlarm
- RTC_C_setCalenderEvent
- RTC_C_definePrescaleEvent
- RTC_C_enableInterrupt

- RTC_C_disableInterrupt
- RTC_C_getInterruptStatus
- RTC_C_clearInterrupt

The RTC_C data conversion is handled by

- RTC_C_convertBCDToBinary
- RTC_C_convertBinaryToBCD

27.3 Programming Example

The following example shows how to initialize and use the RTC_C API to setup Calender Mode with the current time and various interrupts.

```
  //Initialize Calendar Mode of RTC_C
    /*
 Base Address of the RTC_C_A
 Pass in current time, intialized above
 Use BCD as Calendar Register Format
     */
    RTC_C_calendarInit(RTC_C_BASE,
        currentTime,
        RTC_C_FORMAT_BCD);

    //Setup Calendar Alarm for 5:00pm on the 5th day of the week.
    //Note: Does not specify day of the week.
    RTC_C_setCalendarAlarm(RTC_C_BASE,
        0x00,
        0x17,
        RTC_C_ALARMCONDITION_OFF,
        0x05);

    //Specify an interrupt to assert every minute
    RTC_C_setCalendarEvent(RTC_C_BASE,
        RTC_C_CALENDAREVENT_MINUTECHANGE);

    //Enable interrupt for RTC_C Ready Status, which asserts when the RTC_C
    //Calendar registers are ready to read.
    //Also, enable interrupts for the Calendar alarm and Calendar event.
    RTC_C_enableInterrupt(RTC_C_BASE,
        RTC_CRDYIE + RTC_CTEVIE + RTC_CAIE);

    //Start RTC_C Clock
    RTC_C_startClock(RTC_C_BASE);

    //Enter LPM3 mode with interrupts enabled
    __bis_SR_register(LPM3_bits + GIE);
    __no_operation();
```

28 24-Bit Sigma Delta Converter (SD24_B)

Introduction 81
API Functions 81
Programming Example 82

28.1 Introduction

The SD24_B module consists of up to eight independent sigma-delta analog-to-digital converters. The converters are based on second-order oversampling sigma-delta modulators and digital decimation filters. The decimation filters are comb type filters with selectable oversampling ratios of up to 1024. Additional filtering can be done in software.

A sigma-delta analog-to-digital converter basically consists of two parts: the analog part

- called modulator - and the digital part - a decimation filter. The modulator of the SD24_B provides a bit stream of zeros and ones to the digital decimation filter. The digital filter averages the bitstream from the modulator over a given number of bits (specified by the oversampling rate) and provides samples at a reduced rate for further processing to the CPU.

As commonly known averaging can be used to increase the signal-to-noise performance of a conversion. With a conventional ADC each factor-of-4 oversampling can improve the SNR by about 6 dB or 1 bit. To achieve a 16-bit resolution out of a simple 1-bit ADC would require an impractical oversampling rate of 415 = 1.073.741.824. To overcome this limitation the sigma-delta modulator implements a technique called noise-shaping - due to an implemented feedback-loop and integrators the quantization noise is pushed to higher frequencies and thus much lower oversampling rates are sufficient to achieve high resolutions.

This driver is contained in `sd24_b.c`, with `sd24_b.h` containing the API definitions for use by applications.

28.2 API Functions

The SD24_B API is broken into three groups of functions: those that deal with initialization and conversions, those that handle interrupts, and those that handle auxillary features of the SD24_B.

The SD24_B initialization and conversion functions are

- SD24_B_init
- SD24_B_configureConverter
- SD24_B_configureConverterAdvanced
- SD24_B_startGroupConversion
- SD24_B_stopGroupConversion
- SD24_B_stopConverterConversion
- SD24_B_startConverterConversion
- SD24_B_configureDMATrigger
- SD24_B_getResults

- SD24_B_getHighWordResults

The SD24_B interrupts are handled by

- SD24_B_enableInterrupt
- SD24_B_disableInterrupt
- SD24_B_clearInterrupt
- SD24_B_getInterruptStatus

Auxilary features of the SD24_B are handled by

- SD24_B_setConverterDataFormat
- SD24_B_setInterruptDelay
- SD24_B_setOversampling
- SD24_B_setGain

28.3 Programming Example

The following example shows how to initialize and use the SD24_B API to start a single channel, single conversion.

```
        unsigned long results;

        SD24_B_init(SD24_BASE,
               SD24_B_CLOCKSOURCE_SMCLK,
               SD24_B_PRECLOCKDIVIDER_1,
               SD24_B_CLOCKDIVIDER_1,
               SD24_B_REF_INTERNAL);                    // Select internal REF
                                                // Select SMCLK as SD24_B clock source

        SD24_B_configureConverter(SD24_BASE,
                       SD24_B_CONVERTER_2,
                       SD24_B_ALIGN_RIGHT,
                       SD24_B_CONVERSION_SELECT_SD24SC,
                       SD24_B_SINGLE_MODE);

    __delay_cycles(0x3600);                 // Delay for 1.5V REF startup

    while (1)
    {
        SD24_B_startConverterConversion(SD24_BASE,
                SD24_B_CONVERTER_2);                                                    // Set

        // Poll interrupt flag for channel 2
        while( SD24_B_getInterruptStatus(SD24_BASE,
                       SD24_B_CONVERTER_2
                       SD24_CONVERTER_INTERRUPT) == 0 );

        results = SD24_B_getResults(SD24_BASE,
                SD24_B_CONVERTER_2);                                  // Save CH2 results (clears IFG)

        __no_operation();                   // SET BREAKPOINT HERE
    }
```

29 SFR Module

Introduction 83
API Functions 83
Programming Example 83

29.1 Introduction

The Special Function Registers API provides a set of functions for using the MSP430Ware SFR module. Functions are provided to enable and disable interrupts and control the ~RST/NMI pin

The SFR module can enable interrupts to be generated from other peripherals of the device.

This driver is contained in `sfr.c`, with `sfr.h` containing the API definitions for use by applications.

29.2 API Functions

The SFR API is broken into 2 groups: the SFR interrupts and the SFR ~RST/NMI pin control

The SFR interrupts are handled by

- SFR_enableInterrupt
- SFR_disableInterrupt
- SFR_getInterruptStatus
- SFR_clearInterrupt

The SFR ~RST/NMI pin is controlled by

- SFR_setResetPinPullResistor
- SFR_setNMIEdge
- SFR_setResetNMIPinFunction

29.3 Programming Example

The following example shows how to initialize and use the SFR API

```
do
  {

       // Clear SFR Fault Flag
    SFR_clearInterrupt(SFR_BASE,
                       OFIFG);

    // Test oscillator fault flag
  }while (SFR_getInterruptStatus(SFR_BASE,OFIFG));
```

30 SYS Module

Introduction 85
API Functions 85
Programming Example ..... ??

30.1 Introduction

The System Control (SYS) API provides a set of functions for using the MSP430Ware SYS module. Functions are provided to control various SYS controls, setup the BSL, and control the JTAG Mailbox.

This driver is contained in `sys.c`, with `sys.h` containing the API definitions for use by applications.

30.2 API Functions

The SYS API is broken into 3 groups: the various SYS controls, the BSL controls, and the JTAG mailbox controls.

The various SYS controls are handled by

- SYS_enableDedicatedJTAGPins
- SYS_getBSLEntryIndication
- SYS_enablePMMAccessProtect
- SYS_enableRAMBasedInterruptVectors
- SYS_disableRAMBasedInterruptVectors

The BSL controls are handled by

- SYS_enableBSLProtect
- SYS_disableBSLProtect
- SYS_disableBSLMemory
- SYS_enableBSLMemory
- SYS_setRAMAssignedToBSL
- SYS_setBSLSize

The JTAG Mailbox controls are handled by

- SYS_JTAGMailboxInit
- SYS_getJTAGMailboxFlagStatus
- SYS_getJTAGInboxMessage16Bit
- SYS_getJTAGInboxMessage32Bit
- SYS_setJTAGOutgoingMessage16Bit
- SYS_setJTAGOutgoingMessage32Bit
- SYS_clearJTAGMailboxFlagStatus

30.3 Programming Example

The following example shows how to initialize and use the SYS API

```
SYS_enableBSLProtect(SYS_BASE);
```

31 TEC

Introduction 87
API Functions 87
Programming Example 88

31.1 Introduction

Timer Event Control (TEC) module is the interface between Timer modules and the external events. This chapter describes the TEC Module.

TEC is a module that connects different Timer modules to each other and routes the external signals to the Timer modules. TEC contains the control registers to configure the routing between the Timer modules, and it also has the enable register bits and the interrupt enable and interrupt flags for external event inputs. TEC features include:

- Enabling of internal and external clear signals
- Routing of internal signals (between Timer_D instances) and external clear signals
- Support of external fault input signals
- Interrupt vector generation of external fault and clear signals.
- Generating feedback signals to the Timer capture/compare channels to affect the timer outputs

This driver is contained in `tec.c`, with `tec.h` containing the API definitions for use by applications.

31.2 API Functions

The tec configuration is handled by

- TEC_configureExternalClearInput()
- TEC_configureExternalFaultInput()
- TEC_enableExternalFaultInput()
- TEC_disableExternalFaultInput()
- TEC_enableExternalClearInput()
- TEC_disableExternalClearInput()
- TEC_enableAuxiliaryClearSignal()
- TEC_disableAuxiliaryClearSignal()

The interrupt and status operations are handled by

- TEC_enableExternalFaultInput()
- TEC_disableExternalFaultInput()
- TEC_clearInterruptFlag()
- TEC_getInterruptStatus()

- TEC_enableInterrupt()
- TEC_disableInterrupt()
- TEC_getExternalFaultStatus()
- TEC_clearExternalFaultStatus()
- TEC_getExternalClearStatus()
- TEC_clearExternalClearStatus()

31.3 Programming Example

The following example shows how to use the TEC API.

```
{
  TIMER_D_startCounter(TIMER_D1_BASE,
        TIMERD_UP_MODE);

  // Configure TD1 TEC External Clear
  // Need to physically connect P2.0/TD0.2 to P2.7/TEC1CLR
  GPIO_setAsPeripheralModuleFunctionInputPin(
    GPIO_PORT_P2,
    GPIO_PIN7
    );

  // High Level trigger, ext clear enable
  TEC_configureExternalClearInput(TEC1_BASE,
                                                    TEC_EXTERNAL_CLEAR_SIGNALTYPE_LEVEL_SEN
                                                    TEC_EXTERNAL_CLEAR_SIGNAL_NOT_HELD,
                                                    TEC_EXTERNAL_CLEAR_POLARITY_RISING_EDGE
                                                    );
  TEC_enableExternalClearInput(TEC1_BASE);

}
```

32 TIMER_A

Introduction 89
API Functions 90
Programming Example 90

32.1 Introduction

TIMER_A is a 16-bit timer/counter with multiple capture/compare registers. TIMER_A can support multiple capture/compares, PWM outputs, and interval timing. TIMER_A also has extensive interrupt capabilities. Interrupts may be generated from the counter on overflow conditions and from each of the capture/compare registers.

This peripheral API handles Timer A hardware peripheral.

TIMER_A features include:

- Asynchronous 16-bit timer/counter with four operating modes
- Selectable and configurable clock source
- Up to seven configurable capture/compare registers
- Configurable outputs with pulse width modulation (PWM) capability
- Asynchronous input and output latching
- Interrupt vector register for fast decoding of all Timer interrupts

TIMER_A can operate in 3 modes

- Continuous Mode
- Up Mode
- Down Mode

TIMER_A Interrupts may be generated on counter overflow conditions and during capture compare events.

The TIMER_A may also be used to generate PWM outputs. PWM outputs can be generated by initializing the compare mode with TIMER_A_initCompare() and the necessary parameters. The PWM may be customized by selecting a desired timer mode (continuous/up/upDown), duty cycle, output mode, timer period etc. The library also provides a simpler way to generate PWM using TIMER_A_generatePWM() API. However the level of customization and the kinds of PWM generated are limited in this API. Depending on how complex the PWM is and what level of customization is required, the user can use TIMER_A_generatePWM() or a combination of Timer_initCompare() and timer start APIs

The TIMER_A API provides a set of functions for dealing with the TIMER_A module. Functions are provided to configure and control the timer, along with functions to modify timer/counter values, and to manage interrupt handling for the timer.

Control is also provided over interrupt sources and events. Interrupts can be generated to indicate that an event has been captured.

This driver is contained in `TIMER_A.c`, with `TIMER_A.h` containing the API definitions for use by applications.

32.2 API Functions

The TIMER_A API is broken into three groups of functions: those that deal with timer configuration and control, those that deal with timer contents, and those that deal with interrupt handling.

TIMER_A configuration and initialization is handled by

- TIMER_A_startCounter(),
- TIMER_A_configureContinuousMode(),
- TIMER_A_configureUpMode(),
- TIMER_A_configureUpDownMode(),
- TIMER_A_startContinuousMode(),
- TIMER_A_startUpMode(),
- TIMER_A_startUpDownMode(),
- TIMER_A_initCapture(),
- TIMER_A_initCompare(),
- TIMER_A_clear(),
- TIMER_A_stop()

TIMER_A outputs are handled by

- TIMER_A_getSynchronizedCaptureCompareInput(),
- TIMER_A_getOutputForOutputModeOutBitValue(),
- TIMER_A_setOutputForOutputModeOutBitValue(),
- TIMER_A_generatePWM(),
- TIMER_A_getCaptureCompareCount(),
- TIMER_A_setCompareValue(),
- TIMER_A_getCounterValue()

The interrupt handler for the TIMER_A interrupt is managed with

- TIMER_A_enableInterrupt(),
- TIMER_A_disableInterrupt(),
- TIMER_A_getInterruptStatus(),
- TIMER_A_enableCaptureCompareInterrupt(),
- TIMER_A_disableCaptureCompareInterrupt(),
- TIMER_A_getCaptureCompareInterruptStatus(),
- TIMER_A_clearCaptureCompareInterruptFlag()
- TIMER_A_clearTimerInterruptFlag()

32.3 Programming Example

The following example shows some TIMER_A operations using the APIs

```
{       //Start TIMER_A
    TIMER_A_configureUpDownMode( TIMER_A1_BASE,
        TIMER_A_CLOCKSOURCE_SMCLK,
        TIMER_A_CLOCKSOURCE_DIVIDER_1,
        TIMER_PERIOD,
        TIMER_A_TAIE_INTERRUPT_DISABLE,
        TIMER_A_CCIE_CCR0_INTERRUPT_DISABLE,
        TIMER_A_DO_CLEAR
        );

    TIMER_A_startCounter( TIMER_A1_BASE,
                TIMER_A_UPDOWN_MODE
                );

    //Initialze compare registers to generate PWM1
    TIMER_A_initCompare(TIMER_A1_BASE,
        TIMER_A_CAPTURECOMPARE_REGISTER_1,
        TIMER_A_CAPTURECOMPARE_INTERRUPT_ENABLE,
        TIMER_A_OUTPUTMODE_TOGGLE_SET,
        DUTY_CYCLE1
        );
    //Initialze compare registers to generate PWM2
    TIMER_A_initCompare(TIMER_A1_BASE,
        TIMER_A_CAPTURECOMPARE_REGISTER_2,
        TIMER_A_CAPTURECOMPARE_INTERRUPT_DISABLE,
        TIMER_A_OUTPUTMODE_TOGGLE_SET,
        DUTY_CYCLE2
        );

    //Enter LPM0
    __bis_SR_register(LPM0_bits);

    //For debugger
    __no_operation();
}
```

33 TIMER_B

Introduction 93
API Functions 94
Programming Example 95

33.1 Introduction

TIMER_B is a 16-bit timer/counter with multiple capture/compare registers. TIMER_B can support multiple capture/compares, PWM outputs, and interval timing. TIMER_B also has extensive interrupt capabilities. Interrupts may be generated from the counter on overflow conditions and from each of the capture/compare registers.

This peripheral API handles Timer B harware peripheral.

TIMER_B features include:

- Asynchronous 16-bit timer/counter with four operating modes
- Selectable and configurable clock source
- Up to seven configurable capture/compare registers
- Configurable outputs with pulse width modulation (PWM) capability
- Asynchronous input and output latching
- Interrupt vector register for fast decoding of all Timer_B interrupts

Differences From Timer_A Timer_B is identical to Timer_A with the following exceptions:

- The length of Timer_B is programmable to be 8, 10, 12, or 16 bits
- Timer_B TBxCCRn registers are double-buffered and can be grouped
- All Timer_B outputs can be put into a high-impedance state
- The SCCI bit function is not implemented in Timer_B

TIMER_B can operate in 3 modes

- Continuous Mode
- Up Mode
- Down Mode

TIMER_B Interrupts may be generated on counter overflow conditions and during capture compare events.

The TIMER_B may also be used to generate PWM outputs. PWM outputs can be generated by initializing the compare mode with TIMER_B_initCompare() and the necessary parameters. The PWM may be customized by selecting a desired timer mode (continuous/up/upDown), duty cycle, output mode, timer period etc. The library also provides a simpler way to generate PWM using TIMER_B_generatePWM() API. However the level of customization and the kinds of PWM generated are limited in this API. Depending on how complex the PWM is and what level of customization is required, the user can use TIMER_B_generatePWM() or a combination of Timer_initCompare() and timer start APIs

The TIMER_B API provides a set of functions for dealing with the TIMER_B module. Functions are provided to configure and control the timer, along with functions to modify timer/counter values, and to manage interrupt handling for the timer.

Control is also provided over interrupt sources and events. Interrupts can be generated to indicate that an event has been captured.

This driver is contained in `TIMER_B.c`, with `TIMER_B.h` containing the API definitions for use by applications.

33.2 API Functions

The TIMER_B API is broken into three groups of functions: those that deal with timer configuration and control, those that deal with timer contents, and those that deal with interrupt handling.

TIMER_B configuration and initialization is handled by

- TIMER_B_startCounter(),
- TIMER_B_configureContinuousMode(),
- TIMER_B_configureUpMode(),
- TIMER_B_configureUpDownMode(),
- TIMER_B_startContinuousMode(),
- TIMER_B_startUpMode(),
- TIMER_B_startUpDownMode(),
- TIMER_B_initCapture(),
- TIMER_B_initCompare(),
- TIMER_B_clear(),
- TIMER_B_stop()
- TIMER_B_initCompareLatchLoadEvent(),
- TIMER_B_selectLatchingGroup(),
- TIMER_B_selectCounterLength(),

TIMER_B outputs are handled by

- TIMER_B_getSynchronizedCaptureCompareInput(),
- TIMER_B_getOutputForOutputModeOutBitValue(),
- TIMER_B_setOutputForOutputModeOutBitValue(),
- TIMER_B_generatePWM()
- TIMER_B_getCaptureCompareCount()
- TIMER_B_setCompareValue(),
- TIMER_B_getCounterValue()

The interrupt handler for the TIMER_B interrupt is managed with

- TIMER_B_enableInterrupt(),
- TIMER_B_disableInterrupt(),

- TIMER_B_getInterruptStatus(),
- TIMER_B_enableCaptureCompareInterrupt(),
- TIMER_B_disableCaptureCompareInterrupt(),
- TIMER_B_getCaptureCompareInterruptStatus(),
- TIMER_B_clearCaptureCompareInterruptFlag()
- TIMER_B_clearTimerInterruptFlag()

33.3 Programming Example

The following example shows some TIMER_B operations using the APIs

```
{       //Start TIMER_B
        TIMER_B_configureUpMode(   TIMER_B0_BASE,
          TIMER_B_CLOCKSOURCE_SMCLK,
          TIMER_B_CLOCKSOURCE_DIVIDER_1,
          511,
          TIMER_B_TBIE_INTERRUPT_DISABLE,
          TIMER_B_CCIE_CCR0_INTERRUPT_DISABLE,
          TIMER_B_DO_CLEAR
          );

        TIMER_B_startCounter(   TIMER_B0_BASE,
                TIMER_B_UP_MODE
                );

        //Initialize compare mode to generate PWM1
        TIMER_B_initCompare(TIMER_B0_BASE,
          TIMER_B_CAPTURECOMPARE_REGISTER_1,
          TIMER_B_CAPTURECOMPARE_INTERRUPT_DISABLE,
          TIMER_B_OUTPUTMODE_RESET_SET,
          383
          );

        //Initialize compare mode to generate PWM2
        TIMER_B_initCompare(TIMER_B0_BASE,
          TIMER_B_CAPTURECOMPARE_REGISTER_2,
          TIMER_B_CAPTURECOMPARE_INTERRUPT_ENABLE,
          TIMER_B_OUTPUTMODE_RESET_SET,
          128
          );
}
```

34 TIMER_D

Introduction 97
API Functions 98
Programming Example 100

34.1 Introduction

Timer_D is a 16-bit timer/counter with multiple capture/compare registers. Timer_D can support multiple capture/compares, interval timing, and PWM outputs both in general and high resolution modes. Timer_D also has extensive interrupt capabilities. Interrupts may be generated from the counter on overflow conditions, from each of the capture/compare registers.

This peripheral API handles Timer D handware peripheral.

TIMER_D features include:

- Asynchronous 16-bit timer/counter with four operating modes and four selectable lengths
- Selectable and configurable clock source
- Configurable capture/compare registers
- Controlling rising and falling PWM edges by combining two neighbor TDCCR registers in one compare channel output
- Configurable outputs with PWM capability
- High-resolution mode with a fine clock frequency up to 16 times the timer input clock frequency
- Double-buffered compare registers with synchronized loading
- Interrupt vector register for fast decoding of all Timer_D interrupts

Differences From Timer_B Timer_D is identical to Timer_B with the following exceptions:

- Timer_D supports high-resolution mode.
- Timer_D supports the combination of two adjacent TDCCRx registers in one capture/compare channel.
- Timer_D supports the dual capture event mode.
- Timer_D supports external fault input, external clear input, and signal. See the TEC chapter for detailed information.
- Timer_D can synchronize with a second timer instance when available. See the TEC chapter for detailed information.

TIMER_D can operate in 3 modes

- Continuous Mode
- Up Mode
- Down Mode

TIMER_D Interrupts may be generated on counter overflow conditions and during capture compare events.

The TIMER_D may also be used to generate PWM outputs. PWM outputs can be generated by initializing the compare mode with TIMER_D_initCompare() and the necessary parameters. The PWM may be customized by selecting a desired timer mode (continuous/up/upDown), duty cycle, output mode, timer period etc. The library also provides a simpler way to generate PWM using TIMER_D_generatePWM() API. However the level of customization and the kinds of PWM generated are limited in this API. Depending on how complex the PWM is and what level of customization is required, the user can use TIMER_D_generatePWM() or a combination of TIMER_D_initCompare() and timer start APIs

The TimerD API provides a set of functions for dealing with the TimerD module. Functions are provided to configure and control the timer, along with functions to modify timer/counter values, and to manage interrupt handling for the timer.

Control is also provided over interrupt sources and events. Interrupts can be generated to indicate that an event has been captured.

This driver is contained in `timerd.c`, with `timerd.h` containing the API definitions for use by applications.

34.2 API Functions

The TIMER_D API is broken into three groups of functions: those that deal with timer configuration and control, those that deal with timer contents, and those that deal with interrupt handling.

TimerD configuration and initialization is handled by

- TIMER_D_startCounter(),
- TIMER_D_configureContinuousMode(),
- TIMER_D_configureUpMode(),
- TIMER_D_configureUpDownMode(),
- TIMER_D_startContinuousMode(),
- TIMER_D_startUpMode(),
- TIMER_D_startUpDownMode(),
- TIMER_D_initCapture(),
- TIMER_D_initCompare(),
- TIMER_D_clear(),
- TIMER_D_stop(),
- TIMER_D_configureHighResGeneratorInFreeRunningMode(),
- TIMER_D_configureHighResGeneratorInRegulatedMode(),
- TIMER_D_combineTDCCRToGeneratePWM(),
- TIMER_D_selectLatchingGroup(),
- TIMER_D_selectCounterLength(),
- TIMER_D_initCompareLatchLoadEvent(),
- TIMER_D_disableHighResFastWakeup(),
- TIMER_D_enableHighResFastWakeup(),
- TIMER_D_disableHighResClockEnhancedAccuracy(),

- TIMER_D_enableHighResClockEnhancedAccuracy(),
- TIMER_D_DisableHighResGeneratorForceON(),
- TIMER_D_EnableHighResGeneratorForceON(),
- TIMER_D_selectHighResCoarseClockRange(),
- TIMER_D_selectHighResClockRange()

TimerD outputs are handled by

- TIMER_D_getSynchronizedCaptureCompareInput(),
- TIMER_D_getOutputForOutputModeOutBitValue(),
- TIMER_D_setOutputForOutputModeOutBitValue(),
- TIMER_D_generatePWM(),
- TIMER_D_getCaptureCompareCount(),
- TIMER_D_setCompareValue(),
- TIMER_D_getCaptureCompareLatchCount(),
- TIMER_D_getCaptureCompareInputSignal(),
- TIMER_D_getCounterValue()

The interrupt handler for the TimerD interrupt is managed with

- TIMER_D_enableTimerInterrupt(),
- TIMER_D_disableTimerInterrupt(),
- TIMER_D_getTimerInterruptStatus(),
- TIMER_D_enableCaptureCompareInterrupt(),
- TIMER_D_disableCaptureCompareInterrupt(),
- TIMER_D_getCaptureCompareInterruptStatus(),
- TIMER_D_clearCaptureCompareInterruptFlag()
- TIMER_D_clearTimerInterruptFlag(),
- TIMER_D_enableHighResInterrupt(),
- TIMER_D_disableTimerInterrupt(),
- TIMER_D_getHighResInterruptStatus(),
- TIMER_D_clearHighResInterruptStatus()

Timer_D High Resolution handling APIs

- TIMER_D_getHighResInterruptStatus(),
- TIMER_D_clearHighResInterruptStatus(),
- TIMER_D_disableHighResFastWakeup(),
- TIMER_D_enableHighResFastWakeup(),
- TIMER_D_disableHighResClockEnhancedAccuracy(),
- TIMER_D_enableHighResClockEnhancedAccuracy(),
- TIMER_D_DisableHighResGeneratorForceON(),
- TIMER_D_EnableHighResGeneratorForceON(),
- TIMER_D_selectHighResCoarseClockRange(),
- TIMER_D_selectHighResClockRange(),
- TIMER_D_configureHighResGeneratorInFreeRunningMode(),
- TIMER_D_configureHighResGeneratorInRegulatedMode()

34.3 Programming Example

The following example shows some TimerD operations using the APIs

```
{       //Start TimerD
    TIMER_D_configureUpDownMode( TIMER_A1_BASE,
        TIMER_D_CLOCKSOURCE_SMCLK,
        TIMER_D_CLOCKSOURCE_DIVIDER_1,
        TIMER_PERIOD,
        TIMER_D_TAIE_INTERRUPT_DISABLE,
        TIMER_D_CCIE_CCR0_INTERRUPT_DISABLE,
        TIMER_D_DO_CLEAR
        );

    TIMER_D_startCounter( TIMER_A1_BASE,
                TIMER_D_UPDOWN_MODE
                );

    //Initialze compare registers to generate PWM1
    TIMER_D_initCompare(TIMER_A1_BASE,
        TIMER_D_CAPTURECOMPARE_REGISTER_1,
        TIMER_D_CAPTURECOMPARE_INTERRUPT_ENABLE,
        TIMER_D_OUTPUTMODE_TOGGLE_SET,
        DUTY_CYCLE1
        );
    //Initialze compare registers to generate PWM2
    TIMER_D_initCompare(TIMER_A1_BASE,
        TIMER_D_CAPTURECOMPARE_REGISTER_2,
        TIMER_D_CAPTURECOMPARE_INTERRUPT_DISABLE,
        TIMER_D_OUTPUTMODE_TOGGLE_SET,
        DUTY_CYCLE2
        );

    //Enter LPM0
    __bis_SR_register(LPM0_bits);

    //For debugger
    __no_operation();
}
```

35 Tag Length Value

Introduction 101
API Functions 101
Programming Example 101

35.1 Introduction

The TLV structure is a table stored in flash memory that contains device-specific information. This table is read-only and is write-protected. It contains important information for using and calibrating the device. A list of the contents of the TLV is available in the device-specific data sheet (in the Device Descriptors section), and an explanation on its functionality is available in the MSP430x5xx/MSP430x6xx Family UserŠs Guide

This driver is contained in `tlv.c`, with `tlv.h` containing the API definitions for use by applications.

35.2 API Functions

The APIs that help in querying the information in the TLV structure are listed

- TLV_getInfo() This function retrieves the value of a tag and the length of the tag.
- TLV_getDeviceType() This function retrieves the unique device ID from the TLV structure.
- TLV_getMemory() The returned value is zero if the end of the memory list is reached.
- TLV_getPeripheral() The returned value is zero if the specified tag value (peripheral) is not available in the device.
- TLV_getInterrupt() The returned value is zero is the specified interrupt vector is not defined.

35.3 Programming Example

The following example shows some tlv operations using the APIs

```
struct s_TLV_Die_Record * pDIEREC;
unsigned char bDieRecord_bytes;

TLV_getInfo(TLV_TAG_DIERECORD,
                        0,
                        &bDieRecord_bytes,
                        (unsigned int **)&pDIEREC
                        );
```

36 Unified Clock System (UCS)

Introduction 103
API Functions 104
Programming Example 105

36.1 Introduction

The UCS is based on five available clock sources (VLO, REFO, XT1, XT2, and DCO) providing signals to three system clocks (MCLK, SMCLK, ACLK). Different low power modes are achieved by turning off the MCLK, SMCLK, ACLK, and integrated LDO.

- VLO - Internal very-low-power low-frequency oscillator. 10 kHz (ś0.5/řC, ś4/V)
- REFO - Reference oscillator. 32 kHz (ś1%, ś3% over full temp range)
- XT1 (LFXT1, HFXT1) - Ultra-low-power oscillator, compatible with low-frequency 32768-Hz watch crystals and with standard XT1 (LFXT1, HFXT1) crystals, resonators, or external clock sources in the 4-MHz to 32-MHz range, including digital inputs. Most commonly used as 32-kHz watch crystal oscillator.
- XT2 - Optional high-frequency oscillator that can be used with standard crystals, resonators, or external clock sources in the 4-MHz to 32-MHz range, including digital inputs.
- DCO - Internal digitally-controlled oscillator (DCO) that can be stabilized by a frequency lock loop (FLL) that sets the DCO to a specified multiple of a reference frequency.

System Clocks and Functionality on the MSP430 MCLK Master Clock Services the CPU. Commonly sourced by DCO. Is avaiable in Active mode only SMCLK Subsystem Master Clock Services 'fast' system peripherals. Commonly sourced by DCO. Is available in Active mode, LPM0 and LPM1 ACLK Auxiliary Clock Services 'slow' system peripherals. Commonly used for 32-kHz signal.Is available in Active mode, LPM0 to LPM3

System clocks of the MSP430x5xx generation are automatically enabled, regardless of the LPM mode of operation, if they are required for the proper operation of the peripheral module that they source. This additional flexibility of the UCS, along with improved fail-safe logic, provides a robust clocking scheme for all applications.

Fail-Safe logic The UCS fail-safe logic plays an important part in providing a robust clocking scheme for MSP430x5xx and MSP430x6xx applications. This feature hinges on the ability to detect an oscillator fault for the XT1 in both low- and high-frequency modes (XT1LFOFFG and XT1HFOFFG respectively), the high-frequency XT2 (XT2OFFG), and the DCO (DCOFFG). These flags are set and latched when the respective oscillator is enabled but not operating properly; therefore, they must be explicitly cleared in software

The oscillator fault flags on previous MSP430 generations are not latched and are asserted only as long as the failing condition exists. Therefore, an important difference between the families is that the fail-safe behavior in a 5xx-based MSP430 remains active until both the OFIFG and the respective fault flag are cleared in software.

This fail-safe behavior is implemented at the oscillator level, at the system clock level and, consequently, at the module level. Some notable highlights of this behavior are described below. For the full description of fail-safe behavior and conditions, see the MSP430x5xx/MSP430x6xx Family UserŠs Guide (SLAU208).

- Low-frequency crystal oscillator 1 (LFXT1) The low-frequency (32768 Hz) crystal oscillator is the default reference clock to the FLL. An asserted XT1LFOFFG switches the FLL reference from the failing LFXT1 to the internal 32-kHz REFO. This can influence the DCO accuracy, because the FLL crystal ppm specification is typically tighter than the REFO accuracy over temperature and voltage of ś3%.
- System Clocks (ACLK, SMCLK, MCLK) A fault on the oscillator that is sourcing a system clock switches the source from the failing oscillator to the DCO oscillator (DCOCLKDIV). This is true for all clock sources except the LFXT1. As previously described, a fault on the LFXT1 switches the source to the REFO. Since ACLK is the active clock in LPM3 there is a notable difference in the LPM3 current consumption when the REFO is the clock source ($\sim$3 μA active) versus the LFXT1 ($\sim$300 nA active).
- Modules (WDT_A) In watchdog mode, when SMCLK or ACLK fails, the clock source defaults to the VLOCLK.

This driver is contained in `ucs.c`, with `ucs.h` containing the API definitions for use by applications.

36.2 API Functions

The UCS API is broken into three groups of functions: those that deal with clock configuration and control

General UCS configuration and initialization is handled by

- UCS_clockSignalInit(),
- UCS_initFLLSettle(),
- UCS_enableClockRequest(),
- UCS_disableClockRequest(),
- UCS_SMCLKOff(),
- UCS_SMCLKOn()

External crystal specific configuration and initialization is handled by

- UCS_setExternalClockSource(),
- UCS_LFXT1Start(),
- UCS_HFXT1Start(),
- UCS_bypassXT1(),
- UCS_LFXT1StartWithTimeout(),
- UCS_HFXT1StartWithTimeout(),
- UCS_bypassXT1WithTimeout(),
- UCS_XT1Off(),
- UCS_XT2Start(),
- UCS_XT2Off(),
- UCS_bypassXT2(),
- UCS_XT2StartWithTimeout(),

- UCS_bypassXT2WithTimeout()
- UCS_clearAllOscFlagsWithTimeout()

UCS_setExternalClockSource must be called if an external crystal XT1 or XT2 is used and the user intends to call UCS_getMCLK, UCS_getSMCLK or UCS_getACLK APIs. If not, it is not necessary to invoke this API.

Failure to invoke UCS_clockSignalInit() sets the clock signals to the default modes ACLK default mode - UCS_XT1CLK_SELECT SMCLK default mode - UCS_DCOCLKDIV_SELECT MCLK default mode - UCS_DCOCLKDIV_SELECT

Also fail-safe mode behavior takes effect when a slected mode fails.

The status and configuration query are done by

- UCS_faultFlagStatus(),
- UCS_clearFaultFlag(),
- UCS_getACLK(),
- UCS_getSMCLK(),
- UCS_getMCLK()

36.3 Programming Example

The following example shows some UCS operations using the APIs

```
// Set DCO FLL reference = REFO
  UCS_clockSignalInit(UCS_BASE,
                      UCS_FLLREF,
                      UCS_REFOCLK_SELECT,
                      UCS_CLOCK_DIVIDER_1
                       );
  // Set ACLK = REFO
 UCS_clockSignalInit(UCS_BASE,
                      UCS_ACLK,
                      UCS_REFOCLK_SELECT,
                      UCS_CLOCK_DIVIDER_1
                       );

  // Set Ratio and Desired MCLK Frequency  and initialize DCO
  UCS_initFLLSettle(  UCS_BASE,
                       UCS_MCLK_DESIRED_FREQUENCY_IN_KHZ,
                       UCS_MCLK_FLLREF_RATIO
                     );

  //Verify if the Clock settings are as expected
  clockValue = UCS_getSMCLK (UCS_BASE);

  while(1);
```

37 USCI Universal Asynchronous Receiver/Transmitter (USCI_A_UART)

Introduction 107
API Functions 107
Programming Example 108

37.1 Introduction

The MSP430Ware library for USCI_A_UART mode features include:

- Odd, even, or non-parity
- Independent transmit and receive shift registers
- Separate transmit and receive buffer registers
- LSB-first or MSB-first data transmit and receive
- Built-in idle-line and address-bit communication protocols for multiprocessor systems
- Receiver start-edge detection for auto wake up from LPMx modes
- Status flags for error detection and suppression
- Status flags for address detection
- Independent interrupt capability for receive and transmit

The modes of operations supported by the USCI_A_UART and the library include

- USCI_A_UART mode
- Idle-line multiprocessor mode
- Address-bit multiprocessor mode
- USCI_A_UART mode with automatic baud-rate detection

In USCI_A_UART mode, the USCI transmits and receives characters at a bit rate asynchronous to another device. Timing for each character is based on the selected baud rate of the USCI. The transmit and receive functions use the same baud-rate frequency.

This driver is contained in `usci_a_uart.c`, with `usci_a_uart.h` containing the API definitions for use by applications.

37.2 API Functions

The USCI_A_UART API provides the set of functions required to implement an interrupt driven USCI_A_UART driver. The USCI_A_UART initialization with the various modes and features is done by the USCI_A_UART_init(). At the end of this fucntion USCI_A_UART is initialized and stays disabled. USCI_A_UART_enable() enables the USCI_A_UART and the module is now ready for transmit and receive. It is recommended to iniailize the USCI_A_UART via USCI_A_UART_init(), enable the required interrupts and then enable USCI_A_UART via USCI_A_UART_enable().

The USCI_A_UART API is broken into three groups of functions: those that deal with configuration and control of the USCI_A_UART modules, those used to send and receive data, and those that deal with interrupt handling and those dealing with DMA.

Configuration and control of the USCI_A_UART are handled by the

- USCI_A_UART_init()
- USCI_A_UART_initAdvance()
- USCI_A_UART_enable()
- USCI_A_UART_disable()
- USCI_A_UART_setDormant()
- USCI_A_UART_resetDormant()

Sending and receiving data via the USCI_A_UART is handled by the

- USCI_A_UART_transmitData()
- USCI_A_UART_receiveData()
- USCI_A_UART_transmitAddress()
- USCI_A_UART_transmitBreak()

Managing the USCI_A_UART interrupts and status are handled by the

- USCI_A_UART_enableInterrupt()
- USCI_A_UART_disableInterrupt()
- USCI_A_UART_getInterruptStatus()
- USCI_A_UART_clearInterruptFlag()
- USCI_A_UART_queryStatusFlags()

DMA related

- USCI_A_UART_getReceiveBufferAddressForDMA()
- USCI_A_UART_getTransmitBufferAddressForDMA()

37.3 Programming Example

The following example shows how to use the USCI_A_UART API to initialize the USCI_A_UART, transmit characters, and receive characters.

```
if ( STATUS_FAIL == USCI_A_UART_init (USCI_A0_BASE,
                                      USCI_A_UART_CLOCKSOURCE_SMCLK,
                                      UCS_getSMCLK(UCS_BASE),
                                      BAUD_RATE,
                                      USCI_A_UART_NO_PARITY,
                                      USCI_A_UART_LSB_FIRST,
                                      USCI_A_UART_ONE_STOP_BIT,
                                      USCI_A_UART_MODE,
                                      USCI_A_UART_OVERSAMPLING_BAUDRATE_GENERATION ))
  {
        return;
  }
```

```
  //Enable USCI_A_UART module for operation
  USCI_A_UART_enable (USCI_A0_BASE);

  //Enable Receive Interrupt
  USCI_A_UART_enableInterrupt (USCI_A0_BASE,
                       UCRXIE);

  //Transmit data
  USCI_A_UART_transmitData(USCI_A0_BASE,
                   transmitData++
                     );

  // Enter LPM3, interrupts enabled
  __bis_SR_register(LPM3_bits + GIE);
  __no_operation();
}

//******************************************************************************
//
// This is the USCI_A0 interrupt vector service routine.
//
//******************************************************************************
#pragma vector=USCI_A0_VECTOR
__interrupt void USCI_A0_ISR(void)
{
  switch(__even_in_range(UCA0IV,4))
  {
    // Vector 2 - RXIFG
     case 2:
        // Echo back RXed character, confirm TX buffer is ready first

        // USCI_A0 TX buffer ready?
        while (!USCI_A_UART_interruptStatus(USCI_A0_BASE,
                                    UCTXIFG)
               );

        //Receive echoed data
        receivedData = USCI_A_UART_receiveData(USCI_A0_BASE);

        //Transmit next data
        USCI_A_UART_transmitData(USCI_A0_BASE,
                         transmitData++
                           );

        break;
     default: break;
  }
}
```

TI Information–Selective Disclosure

38 USCI Synchronous Peripheral Interface (USCI_A_SPI)

Introduction 111
API Functions 111
Programming Example 112

38.1 Introduction

The Serial Peripheral Interface Bus or USCI_A_SPI bus is a synchronous serial data link standard named by Motorola that operates in full duplex mode. Devices communicate in master/slave mode where the master device initiates the data frame.

This library provides the API for handling a 3-wire USCI_A_SPI communication

The USCI_A_SPI module can be configured as either a master or a slave device.

The USCI_A_SPI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the SSI module's input clock.

This driver is contained in `usci_a_spi.c`, with `usci_a_spi.h` containing the API definitions for use by applications.

38.2 API Functions

To use the module as a master, the user must call USCI_A_SPI_masterInit() to configure the USCI_A_SPI Master. This is followed by enabling the USCI_A_SPI module using USCI_A_SPI_enable(). The interrupts are then enabled (if needed). **It** is recommended to enable the USCI_A_SPI module before enabling the interrupts. A data transmit is then initiated using USCI_A_SPI_transmitData() and tehn when the receive flag is set, the received data is read using USCI_A_SPI_receiveData() and this indicates that an RX/TX operation is complete.

To use the module as a slave, initialization is done using USCI_A_SPI_slaveInit() and this is followed by enabling the module using USCI_A_SPI_enable(). Following this, the interrupts may be enabled as needed. When the receive flag is set, data is first transmitted using USCI_A_SPI_transmitData() and this is followed by a data reception by USCI_A_SPI_receiveData()

The USCI_A_SPI API is broken into 3 groups of functions: those that deal with status and initialization, those that handle data, and those that manage interrupts.

The status and initialization of the USCI_A_SPI module are managed by

- USCI_A_SPI_masterInit
- USCI_A_SPI_slaveInit
- USCI_A_SPI_disable
- USCI_A_SPI_enable
- USCI_A_SPI_masterChangeClock
- USCI_A_SPI_isBusy

Data handling is done by

- USCI_A_SPI_transmitData
- USCI_A_SPI_receiveData

Interrupts from the USCI_A_SPI module are managed using

- USCI_A_SPI_disableInterrupt
- USCI_A_SPI_enableInterrupt
- USCI_A_SPI_getInterruptStatus
- USCI_A_SPI_clearInterruptFlag

DMA related

- USCI_A_SPI_getReceiveBufferAddressForDMA
- USCI_A_SPI_getTransmitBufferAddressForDMA

38.3 Programming Example

The following example shows how to use the USCI_A_SPI API to configure the USCI_A_SPI module as a master device, and how to do a simple send of data.

```
  //Initialize Master
  returnValue = USCI_A_SPI_masterInit(USCI_A0_BASE, SMCLK, CLK_getSMClk(),
                                 USCI_SPICLK, MSB_FIRST,
                                 CLOCK_POLARITY_INACTIVITYHIGH
                               );

  if(STATUS_FAIL == returnValue)
  {
    return;
  }

  //Enable USCI_A_SPI module
  USCI_A_SPI_enable(USCI_A0_BASE);

  //Enable Receive interrupt
  USCI_A_SPI_enableInterrupt(USCI_A0_BASE, UCRXIE);

  //Configure port pins to reset slave

  // Wait for slave to initialize
  __delay_cycles(100);

  // Initialize data values
  transmitData = 0x00;

  // USCI_A0 TX buffer ready?
  while (!USCI_A_SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

  //Transmit Data to slave
  USCI_A_SPI_transmitData(USCI_A0_BASE, transmitData);

  // CPU off, enable interrupts
  __bis_SR_register(LPM0_bits + GIE);
}
```

```
//******************************************************************************
//
// This is the USCI_B0 interrupt vector service routine.
//
//******************************************************************************
#pragma vector=USCI_A0_VECTOR
__interrupt void USCI_A0_ISR(void)
{
  switch(__even_in_range(UCA0IV,4))
  {
    // Vector 2 - RXIFG
    case 2:
    // USCI_A0 TX buffer ready?
    while (!USCI_A_SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

    receiveData = USCI_A_SPI_receiveData(USCI_A0_BASE);

    // Increment data
    transmitData++;

    // Send next value
    USCI_A_SPI_transmitData(USCI_A0_BASE, transmitData);

    //Delay between transmissions for slave to process information
    __delay_cycles(40);

    break;
     default: break;
  }
}
```

39 USCI Synchronous Peripheral Interface (USCI_B_SPI)

Introduction 115
API Functions 115
Programming Example 116

39.1 Introduction

The Serial Peripheral Interface Bus or USCI_B_SPI bus is a synchronous serial data link standard named by Motorola that operates in full duplex mode. Devices communicate in master/slave mode where the master device initiates the data frame.

This library provides the API for handling a 3-wire USCI_B_SPI communication

The USCI_B_SPI module can be configured as either a master or a slave device.

The USCI_B_SPI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the SSI module's input clock.

This driver is contained in `usci_b_spi.c`, with `usci_b_spi.h` containing the API definitions for use by applications.

39.2 API Functions

To use the module as a master, the user must call USCI_B_SPI_masterInit() to configure the USCI_B_SPI Master. This is followed by enabling the USCI_B_SPI module using USCI_B_SPI_enable(). The interrupts are then enabled (if needed). **It** is recommended to enable the USCI_B_SPI module before enabling the interrupts. A data transmit is then initiated using USCI_B_SPI_transmitData() and tehn when the receive flag is set, the received data is read using USCI_B_SPI_receiveData() and this indicates that an RX/TX operation is complete.

To use the module as a slave, initialization is done using USCI_B_SPI_slaveInit() and this is followed by enabling the module using USCI_B_SPI_enable(). Following this, the interrupts may be enabled as needed. When the receive flag is set, data is first transmitted using USCI_B_SPI_transmitData() and this is followed by a data reception by USCI_B_SPI_receiveData()

The USCI_B_SPI API is broken into 3 groups of functions: those that deal with status and initialization, those that handle data, and those that manage interrupts.

The status and initialization of the USCI_B_SPI module are managed by

- USCI_B_SPI_masterInit
- USCI_B_SPI_slaveInit
- USCI_B_SPI_disable
- USCI_B_SPI_enable
- USCI_B_SPI_masterChangeClock
- USCI_B_SPI_isBusy

Data handling is done by

- USCI_B_SPI_transmitData
- USCI_B_SPI_receiveData

Interrupts from the USCI_B_SPI module are managed using

- USCI_B_SPI_disableInterrupt
- USCI_B_SPI_enableInterrupt
- USCI_B_SPI_getInterruptStatus
- USCI_B_SPI_clearInterruptFlag

DMA related

- USCI_B_SPI_getReceiveBufferAddressForDMA
- USCI_B_SPI_getTransmitBufferAddressForDMA

39.3 Programming Example

The following example shows how to use the USCI_B_SPI API to configure the USCI_B_SPI module as a master device, and how to do a simple send of data.

```
  //Initialize Master
  returnValue = USCI_B_SPI_masterInit(USCI_A0_BASE, SMCLK, CLK_getSMClk(),
                                 USCI_SPICLK, MSB_FIRST,
                                 CLOCK_POLARITY_INACTIVITYHIGH
                               );

  if(STATUS_FAIL == returnValue)
  {
    return;
  }

  //Enable USCI_B_SPI module
  USCI_B_SPI_enable(USCI_A0_BASE);

  //Enable Receive interrupt
  USCI_B_SPI_enableInterrupt(USCI_A0_BASE, UCRXIE);

  //Configure port pins to reset slave

  // Wait for slave to initialize
  __delay_cycles(100);

  // Initialize data values
  transmitData = 0x00;

  // USCI_A0 TX buffer ready?
  while (!USCI_B_SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

  //Transmit Data to slave
  USCI_B_SPI_transmitData(USCI_A0_BASE, transmitData);

  // CPU off, enable interrupts
  __bis_SR_register(LPM0_bits + GIE);
}
```

```
//******************************************************************************
//
// This is the USCI_B0 interrupt vector service routine.
//
//******************************************************************************
#pragma vector=USCI_B0_VECTOR
__interrupt void USCI_B0_ISR(void)
{
  switch(__even_in_range(UCA0IV,4))
  {
    // Vector 2 - RXIFG
    case 2:
    // USCI_A0 TX buffer ready?
    while (!USCI_B_SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

    receiveData = USCI_B_SPI_receiveData(USCI_A0_BASE);

    // Increment data
    transmitData++;

    // Send next value
    USCI_B_SPI_transmitData(USCI_A0_BASE, transmitData);

    //Delay between transmissions for slave to process information
    __delay_cycles(40);

    break;
     default: break;
  }
}
```

40 USCI Inter-Integrated Circuit (USCI_B_I2C)

Introduction 119
API Functions 121
Programming Example 122

40.1 Introduction

The Inter-Integrated Circuit (USCI_B_I2C) API provides a set of functions for using the MSP430Ware USCI_B_I2C modules. Functions are provided to initialize the USCI_B_I2C modules, to send and receive data, obtain status, and to manage interrupts for the USCI_B_I2C modules.

The USCI_B_I2C module provide the ability to communicate to other IC devices over an USCI_B_I2C bus. The USCI_B_I2C bus is specified to support devices that can both transmit and receive (write and read) data. Also, devices on the USCI_B_I2C bus can be designated as either a master or a slave. The MSP430Ware USCI_B_I2C modules support both sending and receiving data as either a master or a slave, and also support the simultaneous operation as both a master and a slave. Finally, the MSP430Ware USCI_B_I2C modules can operate at two speeds: Standard (100 kb/s) and Fast (400 kb/s).

USCI_B_I2C module can generate interrupts. The USCI_B_I2C module configured as a master will generate interrupts when a transmit or receive operation is completed (or aborted due to an error). The USCI_B_I2C module configured as a slave will generate interrupts when data has been sent or requested by a master.

40.1.1 Master Operations

To drive the master module, the APIs need to be invoked in the following order

- **USCI_B_I2C_masterInit**
- **USCI_B_I2C_setSlaveAddress**
- **USCI_B_I2C_setMode**
- **USCI_B_I2C_enable**
- **USCI_B_I2C_enableInterrupt** (if interrupts are being used) This may be followed by the APIs for transmit or receive as required

The user must first initialize the USCI_B_I2C module and configure it as a master with a call to USCI_B_I2C_masterInit(). That function will set the clock and data rates. This is followed by a call to set the slave address with which the master intends to communicate with using USCI_B_I2C_setSlaveAddress. Then the mode of operation (transmit or receieve) is chosen using USCI_B_I2C_setMode. The USCI_B_I2C module may now be enabled using USCI_B_I2C_enable. It is recommneded to enable the USCI_B_I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below. APIs that include a timeout can be used to avoid being stuck in an infinite loop if the device is stuck waiting for an IFG flag to be set.

Master Single Byte Transmission

- USCI_B_I2C_masterSendSingleByte

Master Mulitple Byte Transmission

- USCI_B_I2C_masterMultiByteSendStart
- USCI_B_I2C_masterMultiByteSendNext
- USCI_B_I2C_masterMultiByteSendFinish
- USCI_B_I2C_masterMultiByteSendStop

Master Single Byte Reception

- USCI_B_I2C_masterSingleReceiveStart
- USCI_B_I2C_masterSingleReceive

Master Multiple Byte Reception

- USCI_B_I2C_masterMultiByteReceiveStart
- USCI_B_I2C_masterMultiByteReceiveNext
- USCI_B_I2C_masterMultiByteReceiveFinish
- USCI_B_I2C_masterMultiByteReceiveStop

Master Single Byte Transmssion with Timeout

- USCI_B_I2C_masterSendSingleByteWithTimeout

Master Multiple Byte Transmission with Timeout

- USCI_B_I2C_masterMultiByteSendStartWithTimeout
- USCI_B_I2C_masterMultiByteSendNextWithTimeout
- USCI_B_I2C_masterMultiByteReceiveFinishWithTimeout
- USCI_B_I2C_masterMultiByteSendStopWithTimeout

Master Single Byte Receiption with Timeout USCI_B_I2C_masterSingleReceiveStartWithTimeout

For the interrupt-driven transaction, the user must register an interrupt handler for the USCI_B_I2C devices and enable the USCI_B_I2C interrupt.

40.1.2 Slave Operations

To drive the slave module, the APIs need to be invoked in the following order

- **USCI_B_I2C_slaveInit**
- **USCI_B_I2C_setMode**
- **USCI_B_I2C_enable**
- **USCI_B_I2C_enableInterrupt** (if interrupts are being used) This may be followed by the APIs for transmit or receive as required

The user must first call the USCI_B_I2C_slaveInit to initialize the slave module in USCI_B_I2C mode and set the slave address. This is followed by a call to set the mode of operation (transmit or receive).The USCI_B_I2C module may now be enabled using USCI_B_I2C_enable. It is recommneded to enable the USCI_B_I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below.

Slave Transmission API

- USCI_B_I2C_slaveDataPut

Slave Reception API

- USCI_B_I2C_slaveDataGet

For the interrupt-driven transaction, the user must register an interrupt handler for the USCI_B_I2C devices and enable the USCI_B_I2C interrupt.

This driver is contained in `usci_b_i2c.c`, with `usci_b_i2c.h` containing the API definitions for use by applications.

40.2 API Functions

The USCI_B_I2C API is broken into three groups of functions: those that deal with interrupts, those that handle status and initialization, and those that deal with sending and receiving data.

The USCI_B_I2C master and slave interrupts and status are handled by

- USCI_B_I2C_enableInterrupt
- USCI_B_I2C_disableInterrupt
- USCI_B_I2C_clearInterruptFlag
- USCI_B_I2C_getInterruptStatus
- USCI_B_I2C_masterIsStopSent
- USCI_B_I2C_masterIsStartSent

Status and initialization functions for the USCI_B_I2C modules are

- USCI_B_I2C_masterInit
- USCI_B_I2C_enable
- USCI_B_I2C_disable
- USCI_B_I2C_isBusBusy
- USCI_B_I2C_isBusy
- USCI_B_I2C_slaveInit
- USCI_B_I2C_interruptStatus
- USCI_B_I2C_setSlaveAddress
- USCI_B_I2C_setMode

Sending and receiving data from the USCI_B_I2C slave module is handled by

- USCI_B_I2C_slaveDataPut
- USCI_B_I2C_slaveDataGet

Sending and receiving data from the USCI_B_I2C slave module is handled by

- USCI_B_I2C_masterSendSingleByte
- USCI_B_I2C_masterMultiByteSendStart
- USCI_B_I2C_masterMultiByteSendNext
- USCI_B_I2C_masterMultiByteSendFinish
- USCI_B_I2C_masterMultiByteSendStop
- USCI_B_I2C_masterMultiByteReceiveStart
- USCI_B_I2C_masterMultiByteReceiveNext
- USCI_B_I2C_masterMultiByteReceiveFinish
- USCI_B_I2C_masterMultiByteReceiveStop
- USCI_B_I2C_masterSingleReceiveStart
- USCI_B_I2C_masterSingleReceive
- USCI_B_I2C_getReceiveBufferAddressForDMA
- USCI_B_I2C_getTransmitBufferAddressForDMA

DMA related

- USCI_B_I2C_getReceiveBufferAddressForDMA
- USCI_B_I2C_getTransmitBufferAddressForDMA

40.3 Programming Example

The following example shows how to use the USCI_B_I2C API to send data as a master.

```
  // Initialize Master
USCI_B_I2C_masterInit(USCI_B0_BASE, SMCLK, CLK_getSMClk(), USCI_B_I2C_SET_DATA_RATE_400KBPS);

// Specify slave address
USCI_B_I2C_setSlaveAddress(USCI_B0_BASE, SLAVE_ADDRESS);

// Set in transmit mode
USCI_B_I2C_setMode(USCI_B0_BASE, USCI_B_I2C_TRANSMIT_MODE);

//Enable USCI_B_I2C Module to start operations
USCI_B_I2C_enable(USCI_B0_BASE);

while (1)
{
  // Send single byte data.
  USCI_B_I2C_masterSendSingleByte(USCI_B0_BASE, transmitData);

  // Delay until transmission completes
  while(USCI_B_I2C_busBusy(USCI_B0_BASE));

  // Increment transmit data counter
  transmitData++;
}
```

41 WatchDog Timer (WDT_A)

Introduction 123
API Functions 123
Programming Example 123

41.1 Introduction

The Watchdog Timer (WDT_A) API provides a set of functions for using the MSP430Ware WDT_A modules. Functions are provided to initialize the Watchdog in either timer interval mode, or watchdog mode, with selectable clock sources and dividers to define the timer interval.

The WDT_A module can generate only 1 kind of interrupt in timer interval mode. If in watchdog mode, then the WDT_A module will assert a reset once the timer has finished.

This driver is contained in `wdt_a.c`, with `wdt_a.h` containing the API definitions for use by applications.

41.2 API Functions

The WDT_A API is one group that controls the WDT_A module.

- WDT_A_hold
- WDT_A_start
- WDT_A_clearCounter
- WDT_A_watchdogTimerInit
- WDT_A_intervalTimerInit

41.3 Programming Example

The following example shows how to initialize and use the WDT_A API to interrupt about every 32 ms, toggling the LED in the ISR.

```
//Initialize WDT_A module in timer interval mode,
  //with SMCLK as source at an interval of 32 ms.
  WDT_A_intervalTimerInit(WDT_A_BASE,
      WDT_A_CLOCKSOURCE_SMCLK,
      WDT_A_CLOCKDIVIDER_32K);

  //Enable Watchdog Interupt
  SFR_enableInterrupt(SFR_BASE,
      WDT_AIE);

  //Set P1.0 to output direction
  GPIO_setAsOutputPin(
              GPIO_PORT_P1,
      GPIO_PIN0
      );
```

```
//Enter LPM0, enable interrupts
__bis_SR_register(LPM0_bits + GIE);
//For debugger
__no_operation();
```

IMPORTANT NOTICE

Texas Instruments Incorporated and its subsidiaries (TI) reserve the right to make corrections, modifications, enhancements, improvements, and other changes to its products and services at any time and to discontinue any product or service without notice. Customers should obtain the latest relevant information before placing orders and should verify that such information is current and complete. All products are sold subject to TI's terms and conditions of sale supplied at the time of order acknowledgment.

TI warrants performance of its hardware products to the specifications applicable at the time of sale in accordance with TI's standard warranty. Testing and other quality control techniques are used to the extent TI deems necessary to support this warranty. Except where mandated by government requirements, testing of all parameters of each product is not necessarily performed.

TI assumes no liability for applications assistance or customer product design. Customers are responsible for their products and applications using TI components. To minimize the risks associated with customer products and applications, customers should provide adequate design and operating safeguards.

TI does not warrant or represent that any license, either express or implied, is granted under any TI patent right, copyright, mask work right, or other TI intellectual property right relating to any combination, machine, or process in which TI products or services are used. Information published by TI regarding third-party products or services does not constitute a license from TI to use such products or services or a warranty or endorsement thereof. Use of such information may require a license from a third party under the patents or other intellectual property of the third party, or a license from TI under the patents or other intellectual property of TI.

Reproduction of TI information in TI data books or data sheets is permissible only if reproduction is without alteration and is accompanied by all associated warranties, conditions, limitations, and notices. Reproduction of this information with alteration is an unfair and deceptive business practice. TI is not responsible or liable for such altered documentation. Information of third parties may be subject to additional restrictions.

Resale of TI products or services with statements different from or beyond the parameters stated by TI for that product or service voids all express and any implied warranties for the associated TI product or service and is an unfair and deceptive business practice. TI is not responsible or liable for any such statements.

TI products are not authorized for use in safety-critical applications (such as life support) where a failure of the TI product would reasonably be expected to cause severe personal injury or death, unless officers of the parties have executed an agreement specifically governing such use. Buyers represent that they have all necessary expertise in the safety and regulatory ramifications of their applications, and acknowledge and agree that they are solely responsible for all legal, regulatory and safety-related requirements concerning their products and any use of TI products in such safety-critical applications, notwithstanding any applications-related information or support that may be provided by TI. Further, Buyers must fully indemnify TI and its representatives against any damages arising out of the use of TI products in such safety-critical applications.

TI products are neither designed nor intended for use in military/aerospace applications or environments unless the TI products are specifically designated by TI as military-grade or "enhanced plastic." Only products designated by TI as military-grade meet military specifications. Buyers acknowledge and agree that any such use of TI products which TI has not designated as military-grade is solely at the Buyer's risk, and that they are solely responsible for compliance with all legal and regulatory requirements in connection with such use.

TI products are neither designed nor intended for use in automotive applications or environments unless the specific TI products are designated by TI as compliant with ISO/TS 16949 requirements. Buyers acknowledge and agree that, if they use any non-designated products in automotive applications, TI will not be responsible for any failure to meet such requirements.

Following are URLs where you can obtain information on other Texas Instruments products and application solutions:

Products		**Applications**	
Amplifiers	amplifier.ti.com	Audio	www.ti.com/audio
Data Converters	dataconverter.ti.com	Automotive	www.ti.com/automotive
DLP® Products	www.dlp.com	Broadband	www.ti.com/broadband
DSP	dsp.ti.com	Digital Control	www.ti.com/digitalcontrol
Clocks and Timers	www.ti.com/clocks	Medical	www.ti.com/medical
Interface	interface.ti.com	Military	www.ti.com/military
Logic	logic.ti.com	Optical Networking	www.ti.com/opticalnetwork
Power Mgmt	power.ti.com	Security	www.ti.com/security
Microcontrollers	microcontroller.ti.com	Telephony	www.ti.com/telephony
RFID	www.ti-rfid.com	Video & Imaging	www.ti.com/video
RF/IF and ZigBee® Solutions	www.ti.com/lprf	Wireless	www.ti.com/wireless

Mailing Address: Texas Instruments, Post Office Box 655303, Dallas, Texas 75265
Copyright © 2013, Texas Instruments Incorporated